

# Getting Started with GaussianLib

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## Introduction

The GAUSSIANLIB is a simple C++ library for 2D and 3D applications. It provides only basic linear algebra functionality for Vectors, Matrices, and Quaternions.

## Compilation

In the following we consider to have a single C++ file named "Example.cpp". More over %GaussianLibPath% denotes your GaussianLib installation directory.

### GNU/C++

The GAUSSIANLIB requires g++ version 4.8.1 or higher, with C++11 feature set enabled. To compile your application with GNU/C++ (or MinGW on Windows), type this into a command line:

```
g++ -I %GaussianLibPath%/include -std=c++11 Example.cpp -o ExampleOutput
```

If everything worked properly, your executable is named "ExampleOutput".

### VisualC++

The GAUSSIANLIB requires VisualC++ 2013 (12.0) or higher, to support the C++11 features, which are used in the library.

## Vectors

In the GAUSSIANLIB vectors are considered to be **column vectors** per default, as it is common in mathematics. I.e. if you want a vector  $y$  as a result of a multiplication with a matrix  $M$  and a vector  $x$ , write:  $y = M * x$ . To use **row vectors** instead, define the macro GS\_ROW\_VECTORS before you include the library. There are three base classes for vectors: Vector2T<T>, Vector3T<T>, and Vector4T<T>, where <T> specifies the template typename T. There are also pre-defined type aliases ( $N$  is either 2, 3, or 4):

- VectorN Is a type alias to VectorNT<Real>, where Real is either from type float or double.
- VectorNf Is a type alias to VectorNT<float>.
- VectorNd Is a type alias to VectorNT<double>.
- VectorNi Is a type alias to VectorNT<int>.
- VectorNui Is a type alias to VectorNT<unsigned int>.
- VectorNb Is a type alias to VectorNT<char>.
- VectorNub Is a type alias to VectorNT<unsigned char>.

```

#include <Gauss/Gauss.h>
#include <iostream>

int main()
{
    Gs::Vector3 a(1, 2, 3), b(4, 5, 6);

    std::cout << "a = " << a << std::endl;
    std::cout << "b = " << b << std::endl;
    std::cout << "a * b = " << a*b << std::endl;           // Per-component multiplication
    std::cout << "a . b = " << Dot(a, b) << std::endl;     // Dot product (or scalar product)
    std::cout << "a X b = " << Cross(a, b) << std::endl;   // Cross product (or vector product)
    std::cout << "a V b = " << Angle(a, b) << std::endl;   // Vector angle (in radians)
    std::cout << "|a| = " << a.Length() << std::endl;      // Vector length (or norm of the vector)
    std::cout << "|a|^2 = " << a.LengthSq() << std::endl;  // Squared vector length
    std::cout << "a / |a| = " << a.Normalize() << std::endl; // Normalized vector (unit length of 1)

    return 0;
}

```

The vector classes have not been generalized as much as the matrix class. This is due to support the public members `x`, `y`, `z`, and `w`. I.e. you are not restricted to the bracket operator `[]` to access vector components:

```

a.x = 2;
a.z = 3;
a[0] += 2; // equivalent to a.x += 2;

```

## Matrices

There is only a single general-purpose class for matrices (except `AffineMatrix3T` and `AffineMatrix4T`, see section Affine Matrices): `Matrix<T, Rows, Cols>`, where `T` specifies the template typename `T`, `Rows` specifies the number of rows of the matrix, and `Cols` specifies the number of columns of the matrix.

```

#include <Gauss/Gauss.h>
#include <iostream>

int main()
{
    Gs::Matrix4 A;
    A << 1,  0, 2, 0,
        0, -2, 0, 1,
        4,  0, 5, 6,
        0,  1, 0, 1;

    Gs::Matrix<float, 3, 4> B;
    B << 4, 2,  9, -1,
        0, 1,  6,  2,
        3, 7, -2,  0;

    Gs::Matrix<float, 4, 3> C;
    C = B.Transposed();

    Gs::Matrix<float, 3, 3> D;
    D = B*C;

    Gs::Matrix<float, 4, 4> E;
    E = C*B;

    std::cout << "A = " << std::endl << A << std::endl;
    std::cout << "B = " << std::endl << B << std::endl;
    std::cout << "C = " << std::endl << C << std::endl;
    std::cout << "B*C = " << std::endl << D << std::endl;
    std::cout << "C*B = " << std::endl << E << std::endl;

    std::cout << "A^-1 = " << std::endl << A.Inverse() << std::endl;
    std::cout << "A*A^-1 = " << std::endl << A*A.Inverse() << std::endl;
    std::cout << "Trace(A) = " << std::endl << A.Trace() << std::endl;
    std::cout << "Determinant(A) = " << std::endl << A.Determinant() << std::endl;

    return 0;
}

```

## Affine Matrices

In 3D applications a 4x4 matrix is frequently used for affine transformations of 3D models, i.e. translation, rotation, scaling, and sometimes shearing. However, with many 3D models, such transformations require a lot of memory. Moreover, the 4th row of these 4x4 affine matrices is always (0,0,0,1) — except that row vectors are used, where the 4th column is always (0,0,0,1).

To reduce the memory footprint (and some computations), the GAUSSIANLIB provides the `AffineMatrix4T<T>` class, where the 4th row (or column for row-vectors) is implicit, and the `AffineMatrix3T<T>` class, where the 3rd row (or column for row-vectors) is implicit:

```
#include <Gauss/Gauss.h>

int main()
{
    // Affine matrices are always initialized to their identity matrix
    Gs::AffineMatrix4 m;

    m.Translate(Gs::Vector3(0, 4, -2));
    m.RotateX(M_PI*0.5);
    m.RotateFree(Gs::Vector3(1, 1, 1), M_PI*1.5);
    m.Scale(Gs::Vector3(1, 0.5, 2));
    m.MakeInverse();

    Gs::Vector3 v(0, 0, 1);
    auto a = Gs::TransformVector(m, v); // Rotate and Translate (with implicit v.w = 1)
    auto b = Gs::RotateVector(m, v); // Only rotate

    return 0;
}
```

## Quaternions

Quaternions have the four components x, y, z, and w just like `Vector4`. In contrast to vectors, quaternions can only have floating-point components.

```
#include <Gauss/Gauss.h>

int main()
{
    Gs::Quaternion q0, q1; // Equivalent to Gs::QuaternionT<Gs::Real>
    Gs::Quaternionf qFloat;
    Gs::QuaternionT<double> qDouble;

    // Spherical Linear interpolation (SLERP) between q0 and q1
    auto q2 = Gs::Slerp(q0, q1, 0.5);

    // Convert to 3x3 matrix
    Gs::Matrix3 rotation = q2.ToMatrix3();

    // Store rotation of quaternion in the left-upper 3x3 matrix of the sparse 4x4 matrix 'transform'
    Gs::AffineMatrix4 transform;
    Gs::QuaternionToMatrix(transform, q2);

    return 0;
}
```

## Swizzle Operator

For the three vector classes, there is support for the *swizzle operator* (like in shading languages):

```
// Enable 'swizzle operator'
#define GS_ENABLE_SWIZZLE_OPERATOR

#include <Gauss/Gauss.h>

int main()
{
    Gs::Vector4 a, b;
    Gs::Vector3 c, d
```

```

Gs::Vector2 e, f;

e = a.xy();
f = a.zz();
c = a.xxz() + e.yxy()*2.0f;
b = a.xyxy();

// References can not be used (pointless operation).
//a.yz() += e;
//a.zx() *= 2;

a = e.xxyy();
}

```

Every combination is possible!

## Shading Languages

There are two extra header files, which can be included optionally:

```

#define GS_ENABLE_SWIZZLE_OPERATOR
#include <Gauss/Gauss.h>

// Includes all type aliases with name conventions of the DirectX High Level Shading Language HLSL.
#include <Gauss/HLSLTypes.h>

// Includes all type aliases with name conventions of the OpenGL Shading Language (GLSL).
#include <Gauss/GLSLTypes.h>

int main()
{
    // HLSL types
    float4x4 m0;
    double2x3 m1;
    int3 v0;

    // GLSL types
    mat4 m2 = m0;
    ivec2 v1 = v0.yz();
    ivec3 v2 = v0.xxy();

    return 0;
}

```

## Fine Tuning

By default, all vectors, quaternions, and matrices are initialized. To increase performance by not automatically initialize this data, add the following to your compiler pre-defined macros:

```
GS_DISABLE_AUTO_INIT
```

If you don't want to disable the automatic initialization overall, you can explicitly construct a data type who is uninitialized. This can be done with `UninitializeTag`:

```
Gs::Matrix4 m(Gs::UninitializeTag{});
```

`UninitializeTag` is an empty struct, so no memory will be allocated. It's just a hint to the compiler, to call another constructor, which does no initialization. Note, that uninitialized data should always be explicitly marked as such!