Animation and Movie Making

Intended Learning Outcomes

- Distinguish two types of animation
- Describe the four steps of animation
- Describe key frame and intermediate frame generation techniques
- Able to model [illegible] nimation effects such as acceleration, deceler[illegible] periodic motion

Two Types of Animation

- Real time animation
  - Update parts of image in real time as soon as available
- Frame by frame animation
  - Use two fra
  - Display first
  - Update on the second buff
  - Switch the two buffers whe mage has finished drawing on the second buffer
  - Use in system that does not require real time e.g. movie production

Comparisons

- Real time animation
  - Adv. Critical Information displayed as soon as available
  - Disadv. Refresh rate of each pixel must be at least 16 frames/sec to avoid flickering
  - Used in r ht simulator, multi-play

- Frame by frame animation
  - Adv. No flickering even if the refresh rate is low
  - Disadv. Display of information may be delayed up to one frame
  - Used in non-real time systems e.g. movie

Designing an Animation

- Story Board
  - outline of the action. Defines the motion sequence as a set of basic events that are to take place
- Object Definitions

  - choose the object representation and movement of each object in t

- Generation of K

  - generate a detailed image at a certain time in the animation sequence
  - More key frames are specified when the motion is intricate
- Generation of In-between Frames
  - Intermediate frames between the key frames.
  - The number of in-betweens needed is determined by the media to be used to display the animation.

Key frames

From comic “H2”

Generation of in-between frames from key frames

- Key frames can be generated by the CG pipeline
- Morphing can be used to generate in-between frames
- Morphing – short form for metamorphosis
- It is a transfor om one form to another

Morphing

- Step 1 : Equalize the number of vertices of the two shapes
- Step 2 : Find correspondence between each pair of vertices
- Step 3 : Find in [illegible] the vertices by interpolation

Algorithm

Input : Key frames k and k+1

Algorithm

1. Let V_k be the number of vertices in key frame k. Compute

$$V_{\max} = \max(V_k, V_{k+1}) \qquad V_{\min} = \min(V_k, V_{k+1})$$

and

$$N_{ls} = (V_{\max} - 1) \bmod (V_{\min} -$$

$$N_p = \mathrm{int}\left(\frac{V_{\max} - 1}{V_{\min} - 1}\right)$$ // int (x) takes the largest integer

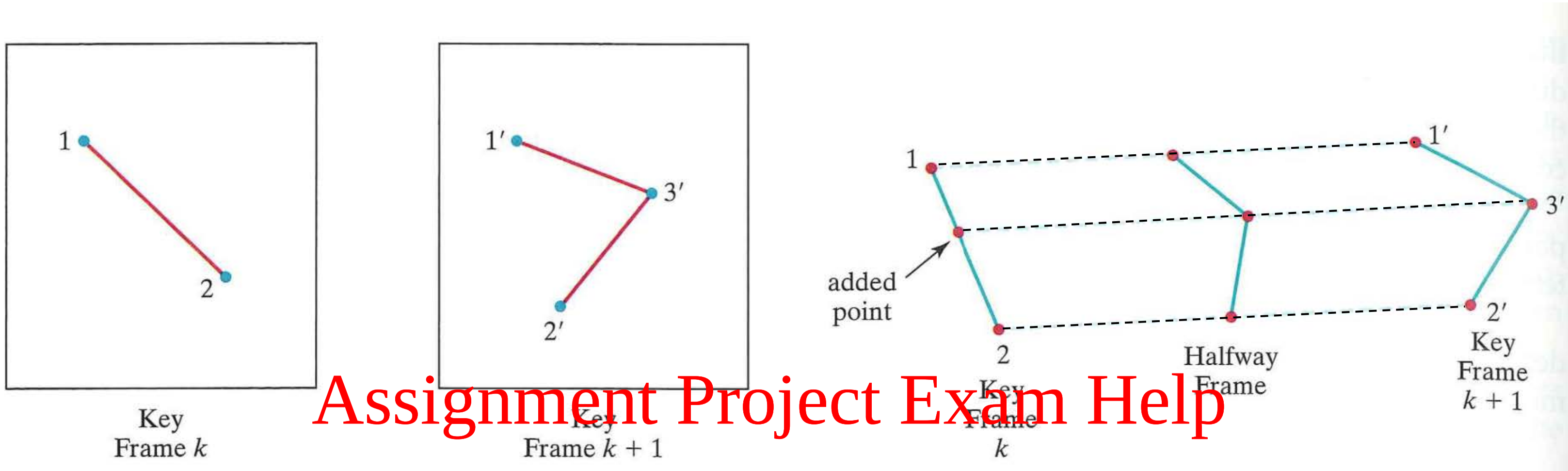
2. Add N_p points to N_{ls} line sections of keyframe$_{\min}$ (the key frame with less number of vertices)

   Add N_p - 1 points to the remaining edges of keyframe$_{\min}$

   // now both key frames have equal number of vertices

3. Linearly interpolate for each pair of corresponding vertices in the two key frames to generate the in-between frames

Output: a set of in-between frames


1
2
Key
Frame k
1′
3′
2′
Key
Frame $k + 1$
1
added
point
2
Key
Frame
k
Halfway
Frame
1′
3′
2′
Key
Frame
$k + 1$

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Simulating Acceleration and Deceleration

- Idea : Adjust the time spacing of successive frames
- n in-between frames for two key frames at t = t_1 and t_2
- Constant veloc

$$tB_j = t_1 + \frac{j\Delta t}{n+1} \qquad \mathrm{j} = 1, 2, \ldots, \mathrm{n} \qquad \Delta t = t_2 - t_1$$

Empirical functions

- Acceleration: Use empirical function 1- cos θ   0< θ < π/2

$$tB_j = t_1 + \Delta t[1 - \cos\frac{j\pi}{2(n+1)}]$$

- Deceleration:

$$tB_j = t_1 + \Delta t[\sin\frac{j\pi}{2(n+1)}]$$

- Accelerate then decelerate: Use $\frac{1}{2}(1 - \cos\theta) \quad 0 < \theta < \pi$

Acceleration

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Deceleration

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Acceleration then Deceleration

Specifying Motion (1)

- For general motions, empirical functions are not accurate enough
- Three ways to calculate motion

  - Direct Motio
    - Solve the just plot the trajectory

    - Example: simple harmo
  - Kinematics and dynamics
    - Kinematics : calculate position, velocity and acceleration

$$v = u + at \qquad s = s_0 + ut + \frac{1}{2}at^2$$

Simple harmonic motion

Specifying Motion (2)

- Inverse Kinematics

  Specify the initial and final conditions, then the system solves for the motion

- Dynamics

  Specify th sed modelling

$$F - kv - h(x - x_0) = ma$$

- Inverse Dynamics

- Goal Directed System
  - Specify desired behaviour : “Walk”, “Run”
  - Converted into mathematical motion by the system

Periodic Motion

- Motion must be synchronized with the frame rate, otherwise may result in incorrect motion
- A typical example is shown in the figures below.
- Solutions
  - Generate a f ngle increment, but this may the periodic motion is too fast
  - Use timer and ask user to have a certain minimum graphics capability in their computer (common practice in games)
  - Periodically reset parameters to prevent numerical error build up

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OpenGL Commands

- Double Buffering
  - *glutInitDisplayMode (GLUT_DOUBLE)*
  - *glutSwapBuffers ( );*

- To produce an animation
  - *glutIdleFunc* [illegible]
  - *animationFc* [illegible] by the user to update the animation para[illegible]
  - *glutPostRedisplay ( );*

- See example program in pg. 410

- Using the timer
  - *glutGet(GLUT_ELAPSED_TIME)*

References

- Text: Ch. 12