3D Hierarchical Modelling

Intended Learning Outcomes

- Understand the need of hierarchical structuring for building articulated 3D objects
- Able to compute the relative coordinate transform between comp
- Able to repres ject as a hierarchical structure using O

Problem:

- Given a large number of graphics models which form parts of a whole object, it is cumbersome to animate each part by individual commands

Example : Animate a car moving at a speed of 20 miles and in direction (2, 3, 4)

```
main ()
{
    float s     = 20.0; /* speed */
    float d[3] = {2.0, 3.0, 4.0}; /* direction */

    draw_chassis (s, d);

    draw_right_front_wheel (s, d);
    draw_left_front_wheel   (s, d);
    draw_right_rear_wheel  (s, d);
    draw_left_rear_wheel    (s, d);

}
```


Tree with directed edge

Bad Programming - Redundancy: the 4 draw wheel functions can be replaced by one function

Introduction of hierarchical structures

- Use *relative transformation* to link the movements of different parts
- Use a single function for a unique (single) part

Directed Acyclic Graph (DAG)

- DAG is a graph with directed arc but no cycle
- It is a tree but additional allows more than one arc fro er node

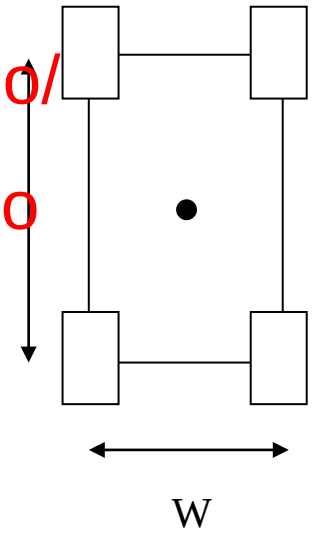
Revised program

```
main ()
{
      float s = 20.0;
      float d[3] ={2.0, 3.0, 4.0};
      float w = 2.0, l = 4.0;       // width and length of the car

      draw_chass (s, d);

      glTranslatef ( w/2 , l/2, 0 );
      draw_wheel (s, d);
     glTranslatef ( -w,     0,  0 );  // position the left front
     draw_wheel (s, d);
     glTranslatef (  0,     -l ,  0 );    // position the left rear wheel
     draw_wheel (s, d);
     glTranslatef ( w,     0,   0  );     // position the right rear wheel
     draw_wheel (s, d);
}
```

Let the initial coordinate system be the centroid of the car



We can make it more systematic by formally introducing coordinate system change, which we do below

Moving a Robot Arm – a 3 level hierarchy

Parts : **base B** (cylinder),

lower arm La (rectangular box)

upper arm Ua (rectangular box)

Arm has 3 degree of fre

B rotate about Y by

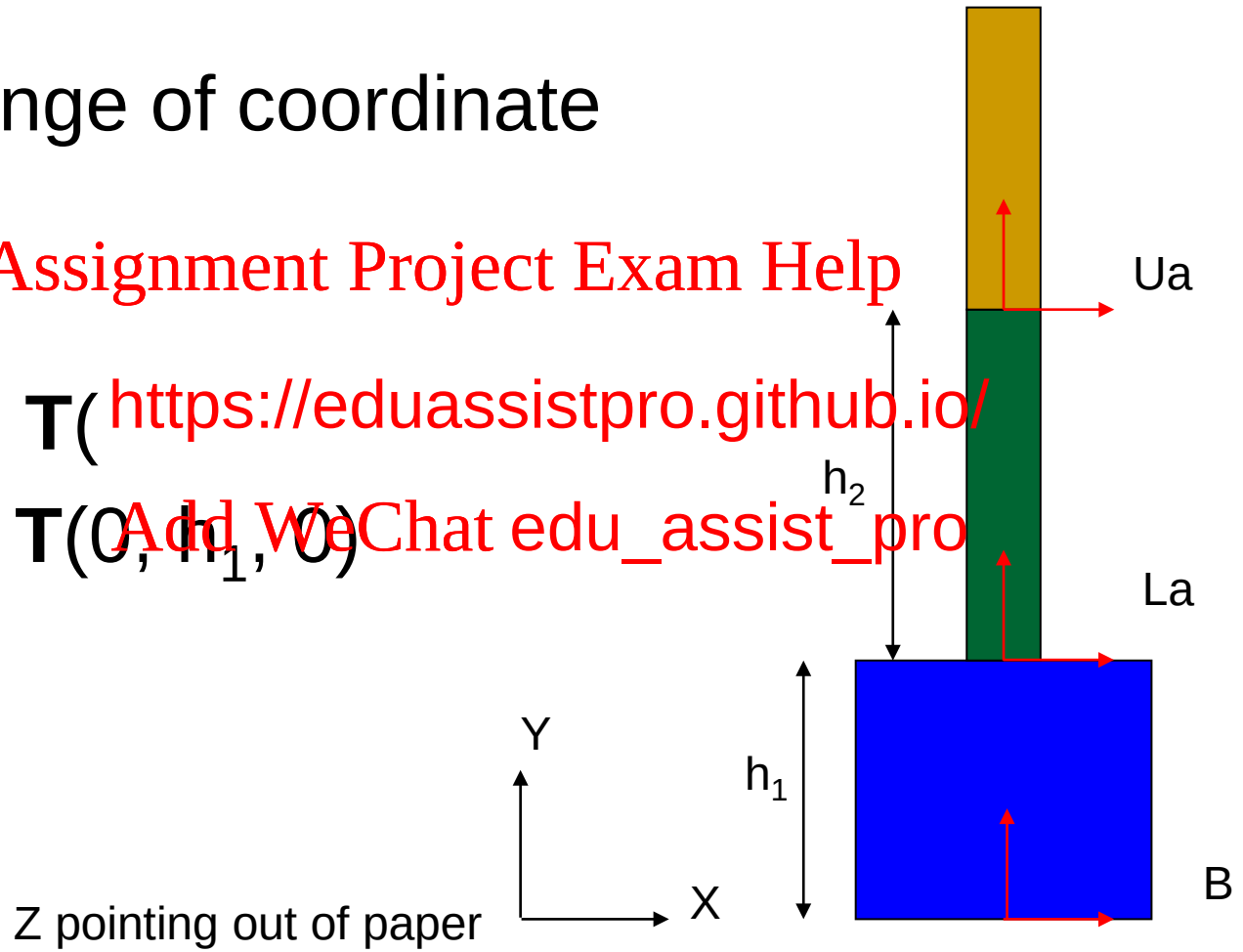
La rotate about Z by ϕ

Ua rotate about Z by ψ

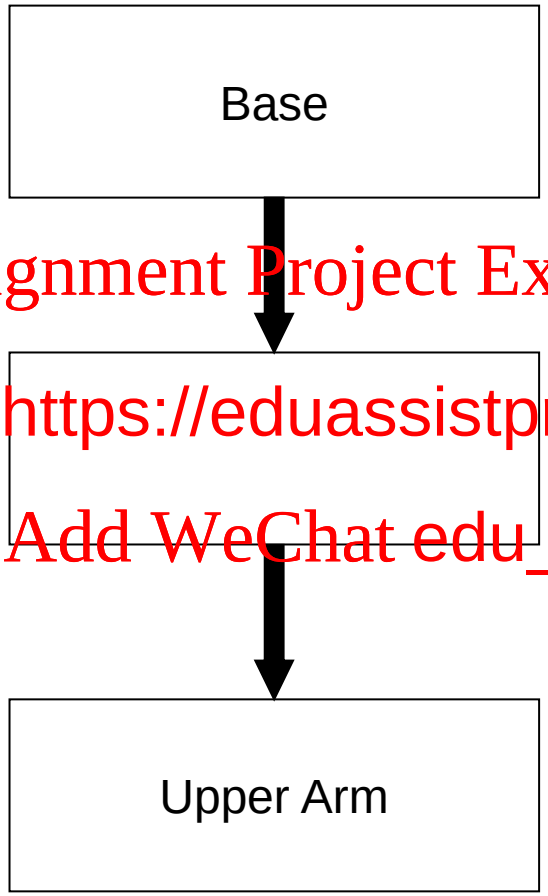
Relative Coordinate Transformations

- Use Change of coordinate system:

- $\mathbf{M}_{La \leftarrow Ua} = \mathbf{T}(0, h_2, 0)$
- $\mathbf{M}_{B \leftarrow La} = \mathbf{T}(0, h_1, 0)$



DAG



Write a program to …

- Rotate the robot arm about its base by θ, then about its lower arm by ϕ, then about its upper arm by ψ

- when rotating t g should move; but when rotati t and the upper arm should move; when rotati er arm, only the upper arm should move.

- Solve this using a hierarchy concept

Program

robot_arm ()
{

glRotatef (theta, 0.0, 1.0, 0.0); // $\mathbf{R}_y(\theta)$ *rotate the whole robot arm*

// *each point of whole robot arm will be pre-multiplied by* $\mathbf{R}_y(\theta)$

base ();

glTranslatef (0.0, h_1*,* *coord. sy. to base coord. sy.*

glRotatef (phi, 0.0, 0

m

// *each point of lower arm will be pre-mult* $0, h_1, 0)\mathbf{R}_z(\phi)$

lower_arm ();

glTranslatef (0.0, h_2*, 0.0);* // $\mathbf{M}_{La \leftarrow Ua}$ *changes upper arm coord. sy. to lower arm coord. sy.*

glRotatef (psi, 0.0, 0.0, 1.0);

// each point of upper arm will be pre-multiplied by $\mathbf{R}_y(\theta)\mathbf{T}(0,h_1,0)\mathbf{R}_z(\phi)\mathbf{T}(0,h_2,0)\mathbf{R}_Z(\psi)$

upper_arm ();

}

Moving a Robot

- Need to organize the hierarchy better
- Solution: use *glPushMatrix* and *glPopMatrix* to store and retrieve intermediate composite relative transformations

Program

```
Robot ()
{
        glPushMatrix ();
        torso;

        glTranslate …
        glRotate …
        head ();

        glPopMatrix ();          /
         glPushMatrix ();

        glTranslate …            /
        glRotate …               // used in example 2
        left_upper_arm ();
        glTranslate …
        glRotate …
        left_lower_arm ();

        glPopMatrix ();          // go back to the node of the torso
         glPushMatrix ();

        glTranslate …
        glRotate …
        right_upper_arm ();

                ⋮
}
```

References

- Our exposition follows:

  E. Angel, Interactive Computer Graphics: A Top-down Approach Using OpenGL, 5th Ed. (2009), Ch. 10.1-10.4

- Ch. 11 of text ference.