Simulating the Rigid World

# Collision Detection

In order to simulate the interactions of rigid shapes, you must first detect which of the shapes are in physical contacts with one another, or, which are the shapes that have collided. In general, there are two important issues to be addressed when working with rigid shape collisions: computation cost and the situations when the shapes overlap, or interpenetrate.

## Broad and Narrow Phase Methods

As discussed when introducing the circular bounds for RigidShape objects, in general every object must be tested for collision with every other object in the game scene. For example, if you want to detect the collisions between five objects, A, B, C, D, and E. You must perform four detection computations for the first object A with B, C, D, and E. With A and B results available, next you must perform three collision detections between the second object, B with objects C, D, and E; followed by two collisions for the third object C, then, one for object D. In this way, without dedicated optimizations, you must perform operations to detect the collisions between objects.

A detailed collision detection algorithm involves intensive computations. This is because accurate results must be computed to support effective interpenetration resolution and realistic collision response simulation. A broad phase method optimizes this computation by exploiting the proximity of objects: the detailed and computationally intensive algorithm, or the narrow phase method, are only deployed for objects that are physically closed to each other.

A popular broad phase method uses axis-aligned bounding boxes (AABB) or bounding circles to approximate proximity of objects. As detailed in Chapter 6, AABBs are excellent for approximating objects that are aligned with the major axes, but, have limitations when objects are rotated. As you have observed from running the previous project with the B key typed, a bounding circle is a circle that centers around and completely bounds an object. By performing the straightforward bounding box/circle intersection computations, it becomes possible to focus only on objects with overlapping bounds as the candidates for narrow phase collision detection operations.

There are other broad phase methods that organize objects either with a spatial structure such as uniform grid or quad-tree or into coherent groups such as hierarchies of bounding colliders. Results from broad phase methods are typically fed into mid phase and finally narrow phase collision detection methods. Each phase narrows down candidates for the eventual collision computation, and each subsequent phase is incrementally more accurate and more expensive.

## Collision Information

In addition to reporting if objects have collided, a collision detection algorithm should also compute and return information that can be used to resolve and respond to the collision.

This information can include penetration depth, and the normal vector of penetration. It is important to compute this information accurately such that the collision can be effectively resolved and the response properly computed to simulate the real world. Remember that object interpenetration does not happen in real world, thus the computed information are only approximation of the actual law of physics.

As illustrated in Figure 3-6, the essential information of a collision includes: collision depth, normal, start, and end. The collision depth is the smallest amount that the objects interpenetrated where the collision normal is the direction along which the collision depth is measured. The start and end are beginning and end positions of the interpenetration defined for the convenience of drawing the interpenetration as a line segment. It is always true that any interpenetration can be resolved by moving the colliding objects along the collision normal by the collision depth distance from the start to the end position. **NEED a new diagram on circle/circle**



Figure 3-6. Collision Information.

## The Circle Collisions and CollisionInfo Project

This project builds the infrastructure for computing and working with collision information based on collisions between circles. As will be discussed, collision information records the specific details of a collision for resolving interpenetration and generating responses. Notice that the bounding circle based broad phase collision detection method computes the exact collision detection solution for rigid circle shapes. For this reason, this project can take advantage of previous project and focus on computing and working with collision information. You can see an example of this project running in Figure 3-7. The source code to this project is defined in the Circle Collision Detection Project folder. This project introduces the rigid shapes and the bounds. You can see an example of this project running in Figure 9-X2. The source code to this project is defined in chapter9/9.2.circle\_collisions\_and\_ colllision\_info.

Figure 9-X1. Running the CollisionInfo and Circle Collisions project

The controls of the project are as follows, for both scenes:

* **This and that**
* **This and that**.

The goals of the project are as follows:

* To understand the implementation of bounding circle collision detection
* To understand the strengths and weaknesses of broad phase collision detection
* To lay the foundation for building a narrow phase collision detection algorithm
* To define collision information
* To build the infrastructure for computing and working with collision information
* To compute and display collision information for circles

You can find the following external resource files in the assets folder: this file and tht file (no changes)

### The Physics Component and Broad Phase Detection

You Physics.js, focus on the loop

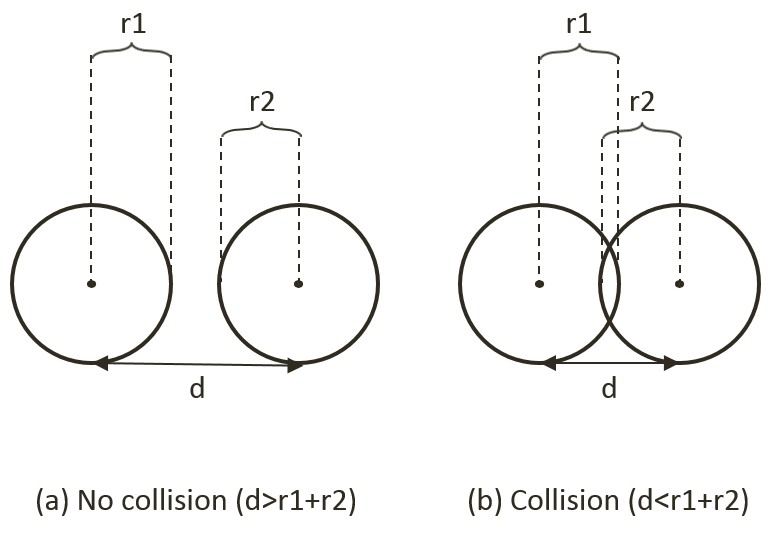


Figure 3-4. Circle Collision Detection: (a) No collision (b) Collision detected.

#### Export Physics to the Client

integrating texture functionality into the engine involves modifying the engine access file, index.js. Edit index.js and add in the following import and export statements to grant client access to this and that

### Define Collision Info

A new class must be defined to support the storage of collision information.

1. Under the SiteRoot/Lib (or public\_html/Lib) folder, create a new file and name it CollisionInfo.js. Remember to load this new source file in index.html.
2. Define the constructor of the object to contain collision depth, collision normal, and a start and end positions. These are the beginning and ending positions of a collision interpenetration.

function CollisionInfo() {

this.mDepth = 0;

this.mNormal = new Vec2(0, 0);

this.mStart = new Vec2(0, 0);

this.mEnd = new Vec2(0, 0);

}

1. Define the getter and setter for the object.

CollisionInfo.prototype.setNormal = function (s) { this.mNormal = s; };

CollisionInfo.prototype.getDepth = function () { return this.mDepth; };

CollisionInfo.prototype.getNormal = function () { return this.mNormal; };

CollisionInfo.prototype.setInfo = function (d, n, s) {

this.mDepth = d;

this.mNormal = n;

this.mStart = s;

this.mEnd = s.add(n.scale(d));

};

1. Create a function to change the direction of the normal. This function will be used to ensure that the normal is always from pointing from the primary to the object that is being tested for collision.

CollisionInfo.prototype.changeDir = function () {

this.mNormal = this.mNormal.scale(-1);

var n = this.mStart;

this.mStart = this.mEnd;

this.mEnd = n;

};

### Compute Collision Information Between Two Circles

In the previous project you implemented the functionality for detecting collisions between two circles. In the following, you will amend the computation of collision information to include the information gained from circle collisions.

1. Create a new file under the SiteRoot/RigidBody (or public\_html/RigidBody) folder, name it Circle\_collision.js. This file will contain the implementation of colliding a rigid circle shape with other rigid shapes.
2. Define the collisionTest function to collide a rigid circle shape with another RigidShape object. Notice that the actual collision testing function is shape specific. For now, a circle only knows how to collide with a circle and will always return false for any other shapes.

Circle.prototype.collisionTest = function (otherShape, collisionInfo) {

var status = false;

if (otherShape.mType === "Circle")

status = this.collidedCircCirc(this, otherShape, collisionInfo);

else

status = false;

return status;

};

1. Define the collideCircCirc function to detect the collision between two circles and to compute the corresponding collision information when a collision is detected. There are three cases to the collision detection: no collision, collision with centers of the two circles located at different, and at exactly the same positions. The following code shows the detection of no collision. The details are depicted in Figure 3-7, vFrom1to2 is the vector pointing from center of c1 to center of c2; rSum is the sum of the radii, and dist is the distance between the centers of two circles.

Circle.prototype.collidedCircCirc = function (c1, c2, collisionInfo) {

var vFrom1to2 = c2.mCenter.subtract(c1.mCenter);

var rSum = c1.mRadius + c2.mRadius;

var dist = vFrom1to2.length();

if (dist > Math.sqrt(rSum \* rSum)) {

return false; //not overlapping

}

// … details in the following steps

};

1. A collision is detected when dist, the distance between the centers of the two circles, is less than the sum of the radii. In this case, if the two circles do not have centers located at the exact same position, the collision depth and normal can be computed. As illustrated in Figure 3-8, since c2 is the reference to the other RigidShape, the collision normal is a vector pointing from c1 towards c2, or in the same direction as vFrom1to2. The collision depth is the difference between rSum and dist, and the start position for c1 is simple c2’s radius distance away from the center of c2 along the normalFrom2to1 direction.



Figure 3-8. Details of a Circle-Circle Collision.

//… continue from the previous step

if (dist !== 0) {

// overlapping but not same position

var normalFrom2to1 = vFrom1to2.scale(-1).normalize();

var radiusC2 = normalFrom2to1.scale(c2.mRadius);

collisionInfo.setInfo(rSum - dist, vFrom1to2.normalize(), c2.mCenter.add(radiusC2));

}

//… details in the next step

1. The last case for two colliding circles is when both circle's centers are located in exactly the same position. In this case, as shown in the following code, the collision normal is defined to be the negative y-direction, and the collision depth is simply the larger of the two radii.

//...continue from the previous step

if (dist !== 0) {

//...identical to previous step

} else {

//same position

if (c1.mRadius > c2.mRadius)

collisionInfo.setInfo(rSum, new Vec2(0, -1),

c1.mCenter.add(new Vec2(0, c1.mRadius)));

else

collisionInfo.setInfo(rSum, new Vec2(0, -1),

c2.mCenter.add(new Vec2(0, c2.mRadius)));

}

### Case for Collision with a Rectangle

The collision computations for a rectangle will be covered later in this chapter. For now, an empty structure will be defined to avoid runtime errors.

1. Create a new file under the SiteRoot/RigidBody (or public\_html/RigidBody) folder, name it Rectangle\_collision.js.
2. Add the following code to the file to return a false condition for all collisions with a rectangle rigid shape for now.

Rectangle.prototype.collisionTest = function (otherShape, collisionInfo) {

var status = false;

if (otherShape.mType === "Circle")

status = false;

else

status = false;

return status;

};

### Testin

### The collision

### Observations

Run Run the project to test your implementation. Notice that when you create two circles, their collision is no longer indicated by a change of color. Instead orange lines are drawn inside the colliding circles to indicate the corresponding collision depth and normal. You can create and observe the collision information drawn on all colliding circles. The collision information will be used to resolve collision interpenetrations. Lastly, observe that collision information is absent from rigid rectangle shapes. This is because you have not implemented the functionality and that the corresponding collisionTest function always returns false. The next two projects will guide you through the implementation of collision computation with rigid rectangle shape.