

# Algorithmes Créatifs

Natural-Artificial environments for  
interactions

Vector Fields and Graphs

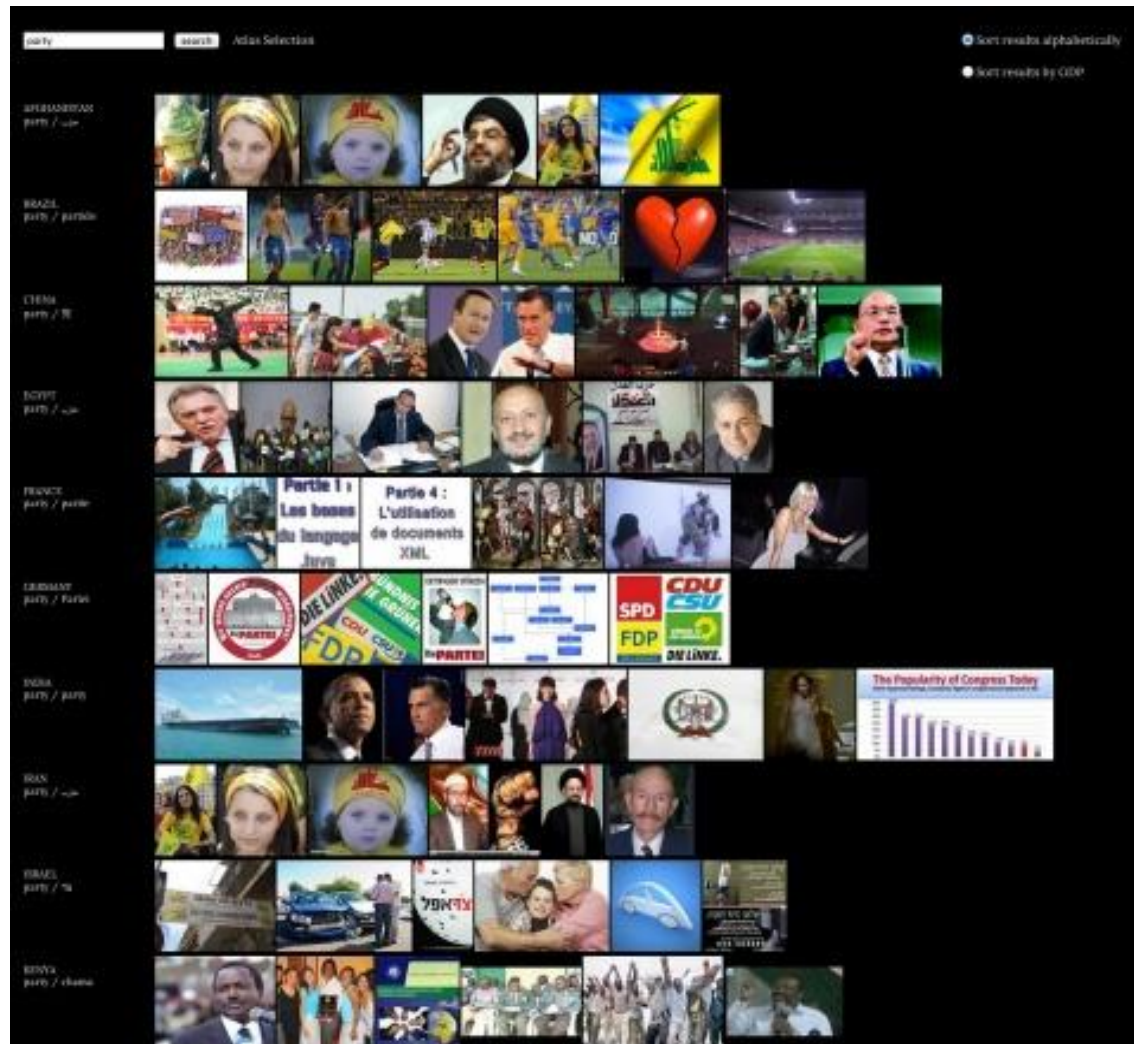
Abelardo G. Fournier

<http://abelardogfournier.org>

@croopier

# Image Atlas

## Taryn Simon & Aaron Swartz



# Sebastian Schmieg

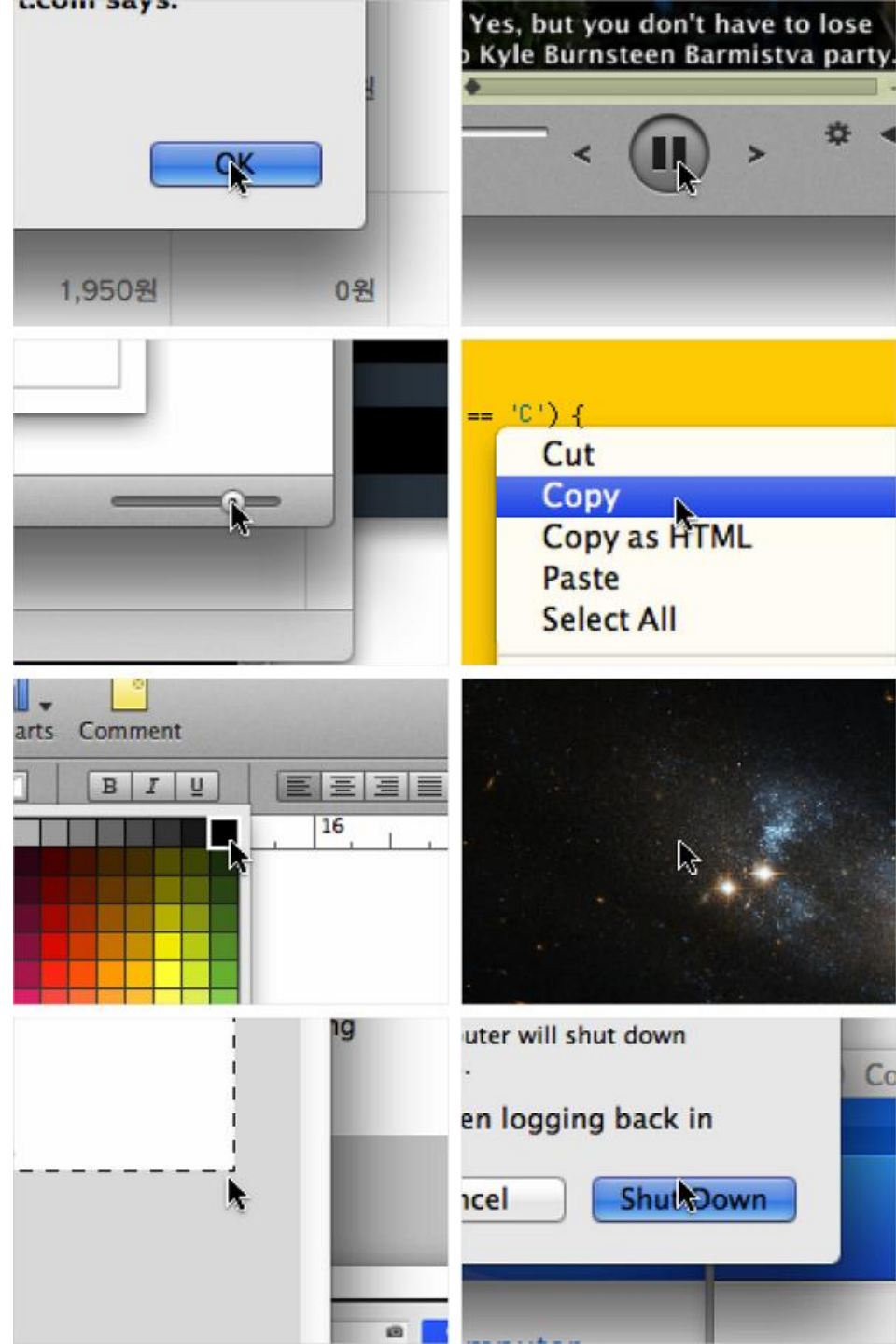


[HTTP://PHOTO.CDN.SOHU.COM/20110603/IMG309201542.JPG](http://photo.cdn.sohu.com/20110603/IMG309201542.JPG)

Search by Image (2011)

# Shinseungback Kimyonghun

Click (2013)

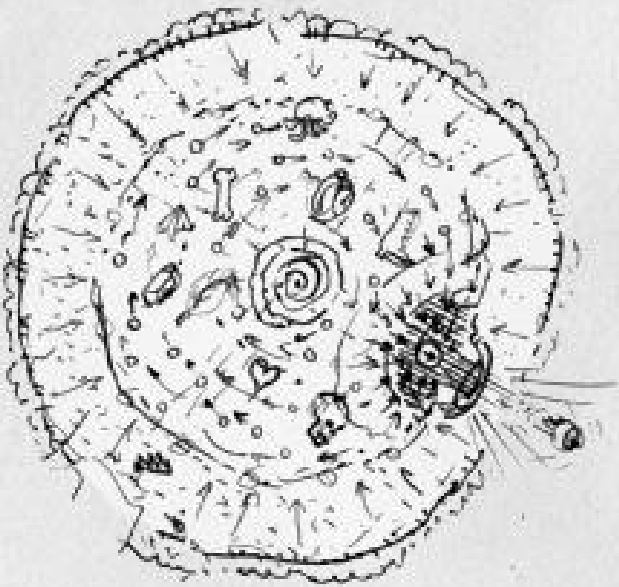


# Shinseungback Kimyonghun



Cloud Face (2012)

# James Paterson - Presstube.com



Cyclic  
Vacuum  
Cannon

[Other projects](#)



# Design I/O - Terrarium

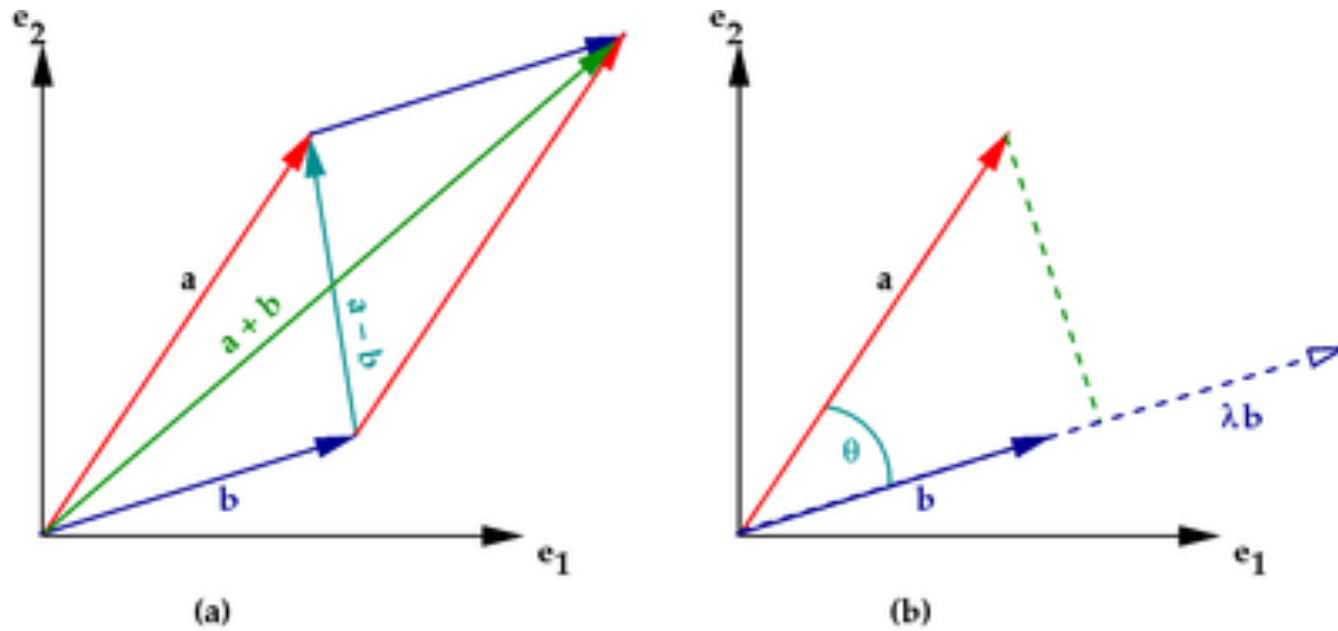


# Toshio Iwai - Electrop plankton





# PVectors



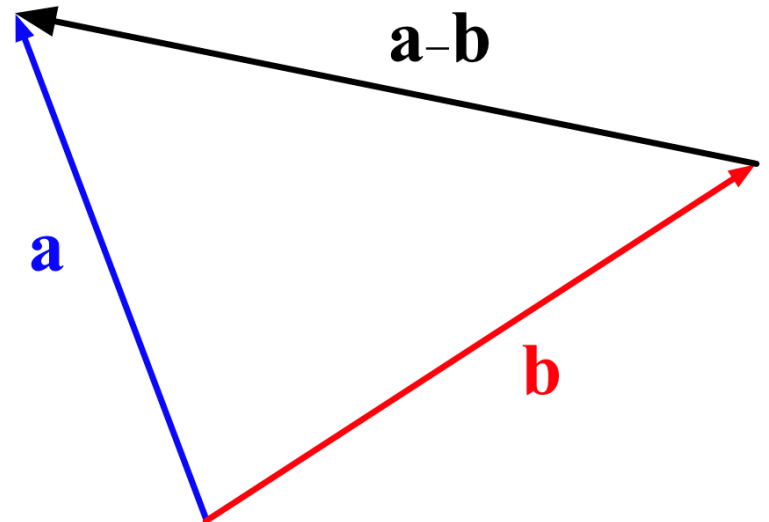
Very useful operations!

heading(), mag(), dist(), setMag(), lerp() ...

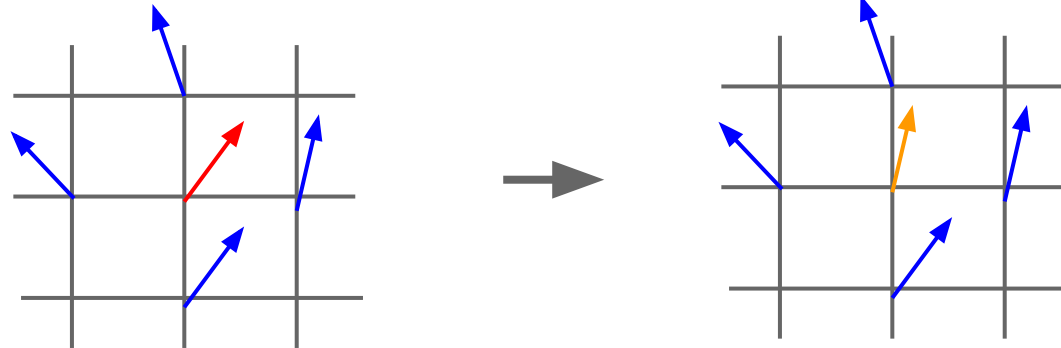
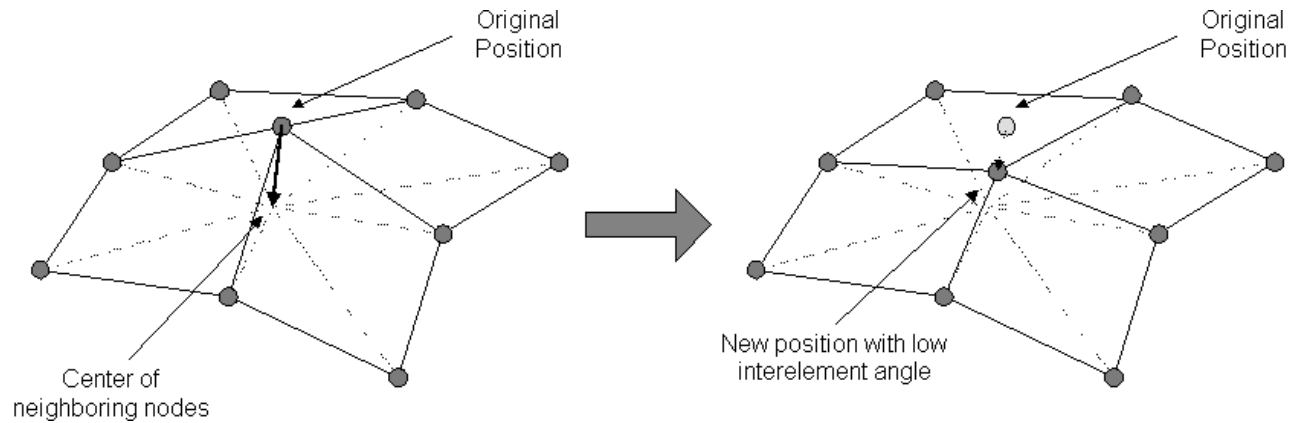
# PVector syntax

Easing algorithm between positions B and A

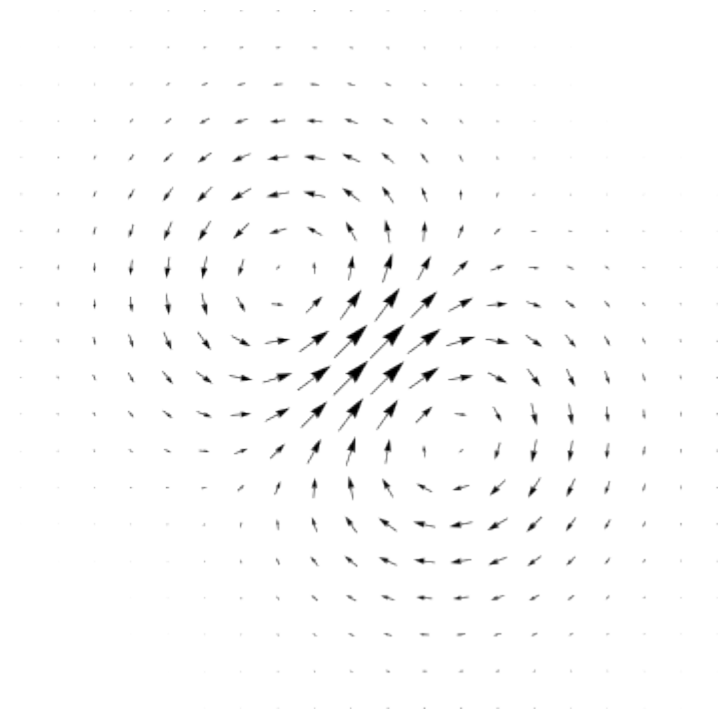
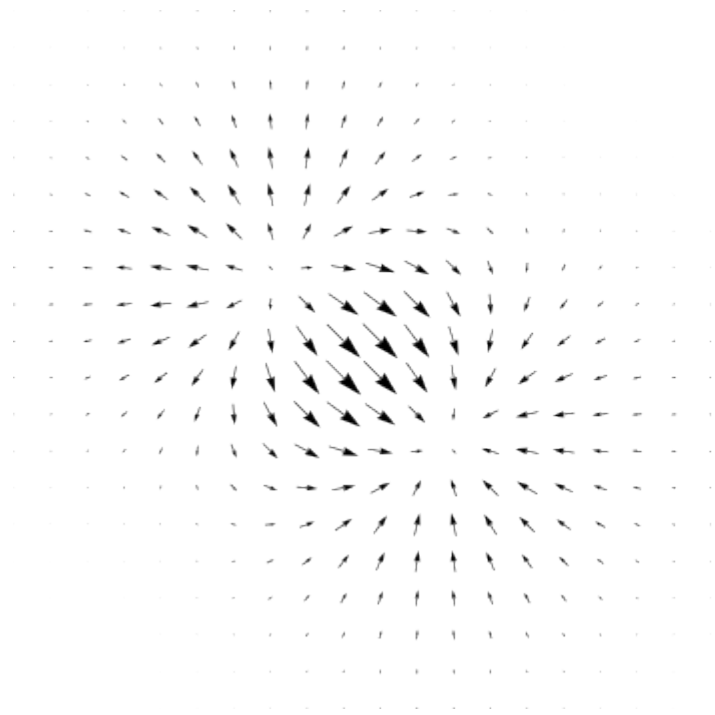
```
PVector next = a.get(); // we grab a copy
next.sub(b); // that's the vector-distance
float dist = next.mag();
// easing:
next.setMag(dist * 0.25);
// finally, next position will be:
next.add(b);
```



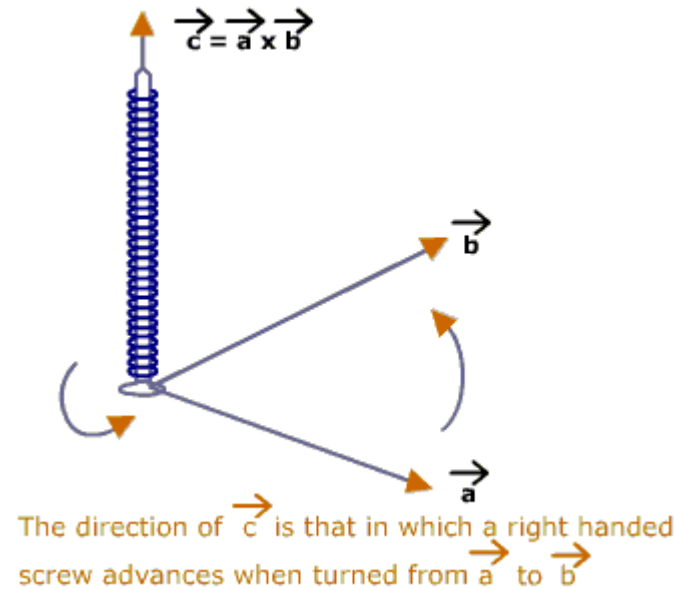
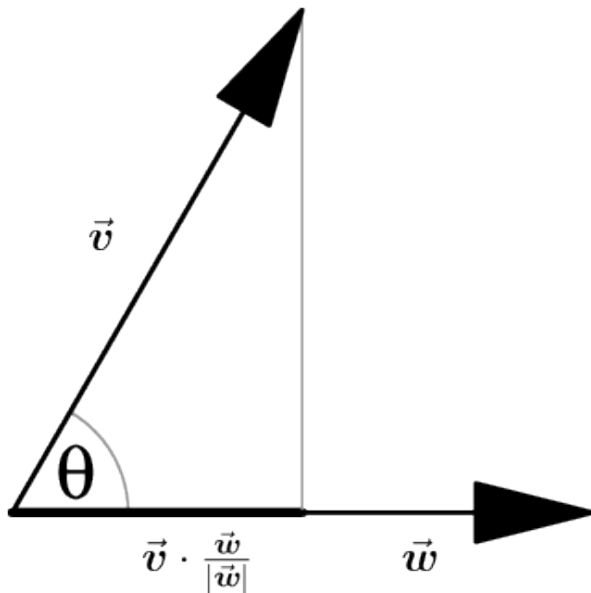
# Smoothing



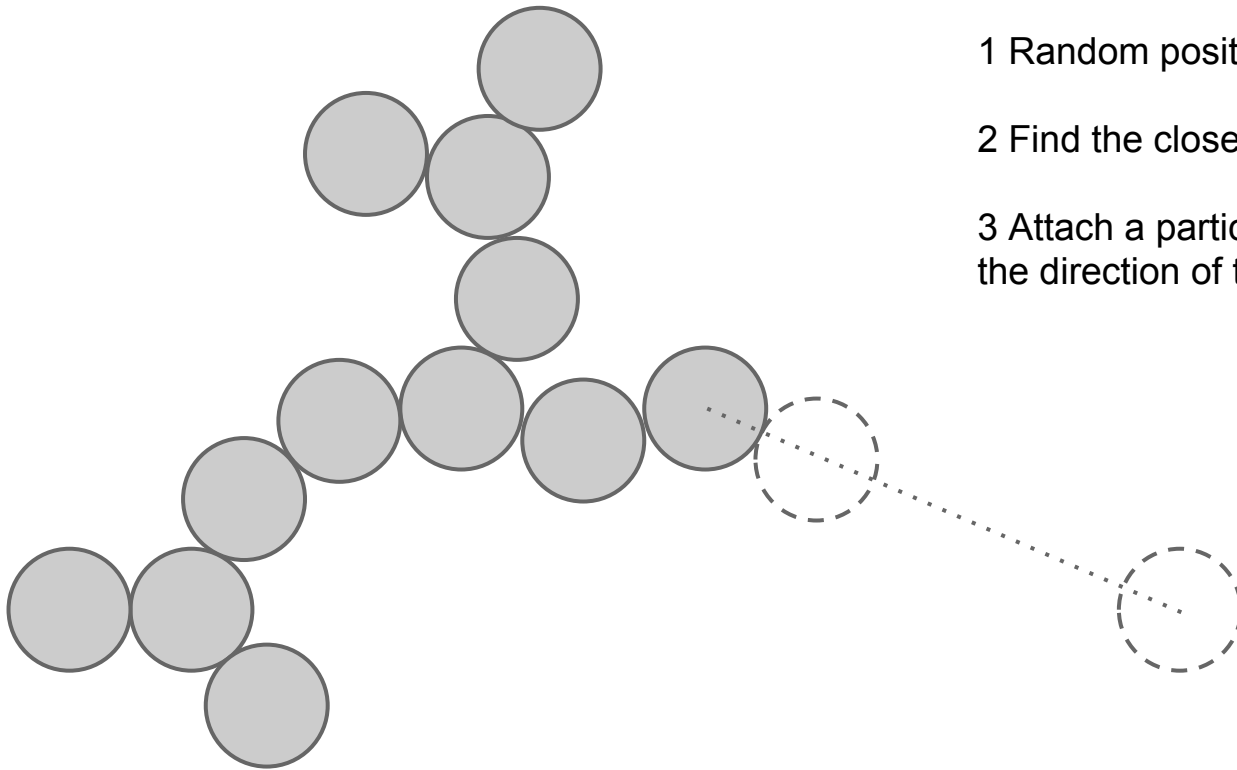
# Divergence and Rotational



# Dot and Cross Product



# DLA algorithm



1 Random position

2 Find the closest particle

3 Attach a particle to the closest in the direction of the initial position



# Physics (traer)

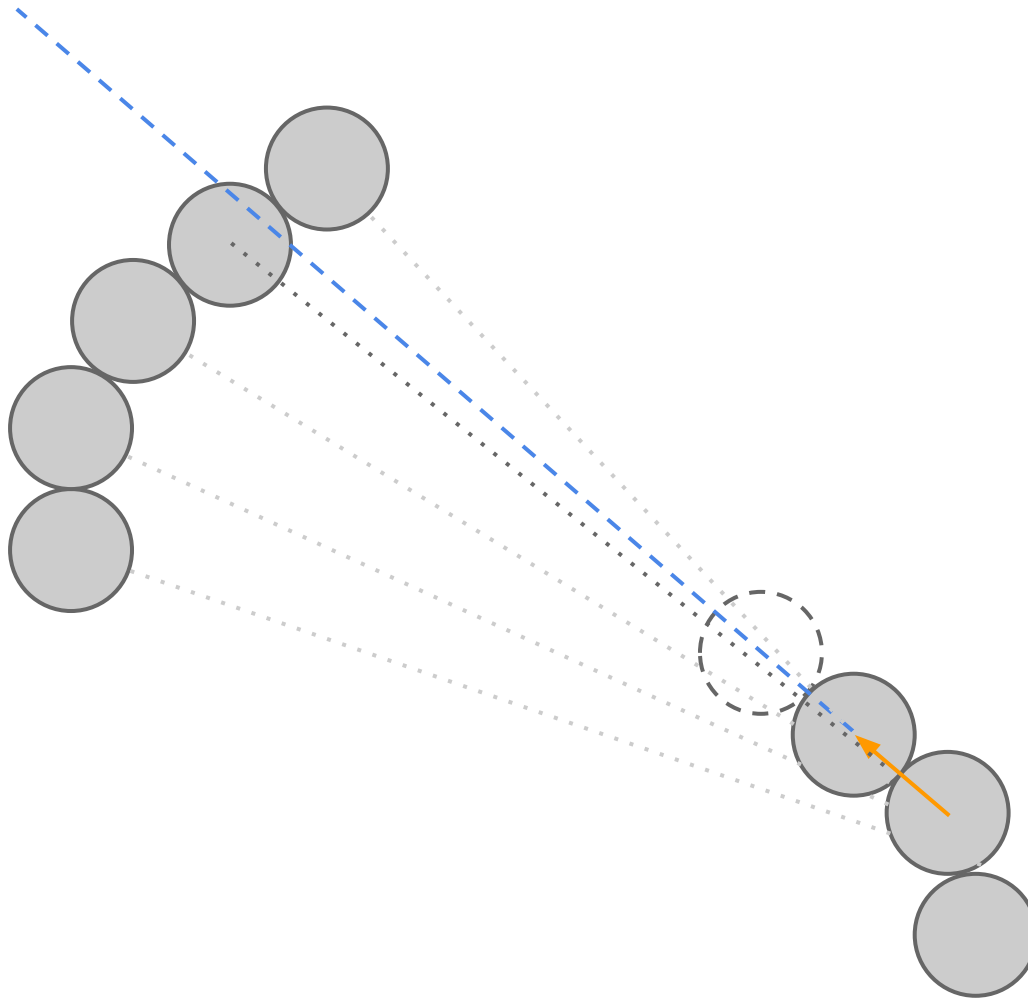
<http://murderandcreate.com/physics/>

```
ParticleSystem physics;  
physics = new ParticleSystem( gravity, friction );  
physics.tick();
```

```
Particle p = physics.makeParticle();  
p.position().set( x, y, z );  
p.position().x() // .y() // .z()
```

```
physics.makeAttraction( p1, p2, -repulsion, min distance );  
physics.makeSpring( p1, p2, strength, damping, rest length );
```

**grow()**



# Path Finder Algorithms

<http://robotacid.com/PBeta/AI/Library/Pathfinder/> (A\*, BFS and Dijkstra)

```
import ai.pathfinder.*;
Pathfinder sys = new Pathfinder();
```

```
Node node = new Node(x, y);
sys.nodes.add( node );
boolean node.walkable
node.connectBoth(node2);
```

```
ArrayList <Node> path =  
    path = sys.bfs(n1, n2);  
Node next = path.get(path.size()-2);
```

