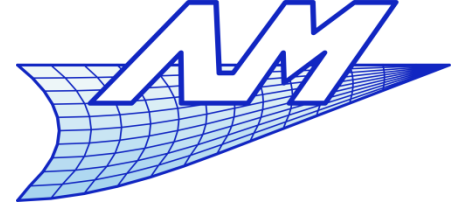
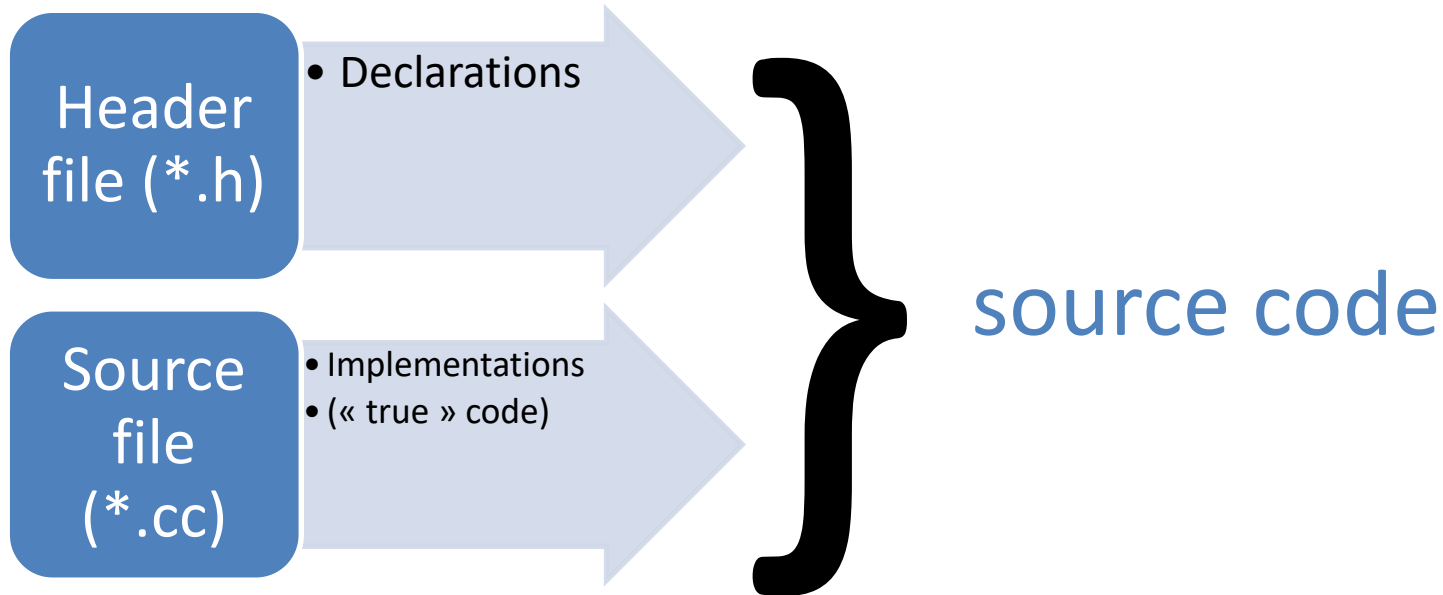


C++ Practical courses

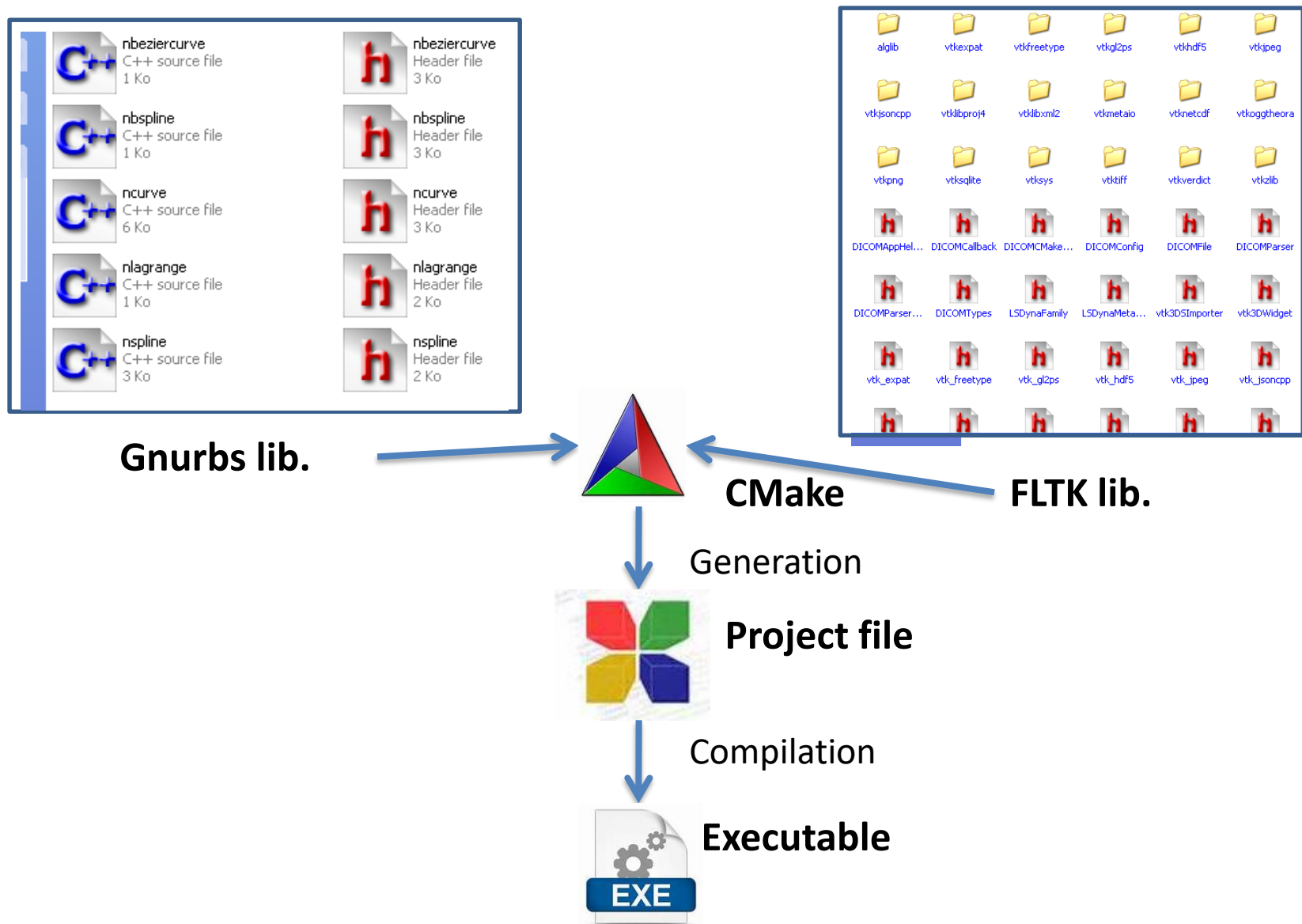


- Who am I?
 - Bolyn Alex(B52/3, +2/...)
 - A.Bolyn@uliege.be
 - Teaching assistant at the A&M department.
- Course web page:
<http://www.cgeo.ulg.ac.be/CADCG/>
 - Schedules, course ressources...
 - Please check-it regularly !

Structure of a C++ project



Structure of a C++ project



Somme references

Book:

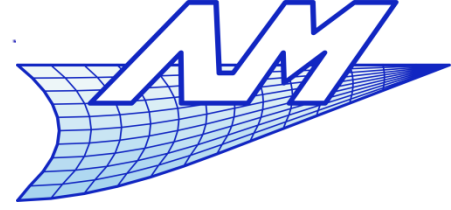
"A Tour of C++", Bjarne Stroustrup

Ed. Addison-Wesley (2013)

ISBN 978-0-321-958310

Website: <https://en.cppreference.com>

(An extensive reference of existing standard functions with examples).



- The interpolation is represented by the following form :

$$P(u) = \sum_{i=0}^{n-1} P_i l_i^p(u) \quad \text{with} \quad l_i^p(u) = \prod_{j=0, j \neq i}^{n-1} \frac{(u - u_j)}{(u_i - u_j)}$$

- Two things worth noting:
 - The curve depends **linearly** on the position of the points
 - It is formed by a weighted sum of **basis functions** that express the influence of each point on the curve

Class nlagrange

```
class nlagrange : public nparametriccurve
```

```
{  
protected:  
    std::vector<double> pos;  
    std::vector<npoint> val;  
    int nCP;
```

Non-reachable from **outside** the class

```
public:
```

```
    nlagrange(int nCP_);  
    virtual int degree(void) const;  
    virtual int nb_CP(void) const;  
    virtual void add_CP(double u_, const npoint &val_);  
    virtual double min_u(void) const;  
    virtual double max_u(void) const;  
    double LagrangeBasis(int which, double u) const;  
    virtual void P(double u_, npoint& ret) const;  
    virtual npoint CP(int which) const;  
    virtual npoint& CP(int which);  
    virtual void set_CP(int which, const npoint& pt);  
    void translate(npoint vec);  
    virtual double u(int which) const;  
    virtual double& u(int which);  
};
```

Reachable
from **outside**
the class.

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;
    int nCP;
public:
    nlagrange(int nCP_);
    virtual int degree(void) const;
    virtual int nb_CP(void) const;
    virtual void add_CP(double u_, const npoint &val_);
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;
public:
    nlagrange(int nCP_);
    virtual int degree(void) const;
    virtual int nb_CP(void) const;
    virtual void add_CP(double u_, const npoint &val_);
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```


Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);
    virtual int degree(void) const;
    virtual int nb_CP(void) const;
    virtual void add_CP(double u_, const npoint &val_);
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;
    virtual int nb_CP(void) const;
    virtual void add_CP(double u_, const npoint &val_);
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;
    virtual void add_CP(double u_, const npoint &val_);
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;    ← Get the maximum u (read-only)
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;    ← Get the maximum u (read-only)
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;    ← Get point on curve
                                                    of parameter u_
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```


Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;    ← Get the maximum u (read-only)
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;    ← Get point on curve
    virtual npoint CP(int which) const;    ← of parameter u_
    virtual npoint& CP(int which);    ← Get CP nr. 'which'
    virtual void set_CP(int which, const npoint& pt);
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;    ← Get the maximum u (read-only)
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;    ← Get point on curve
                                                    of parameter u_
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);    ← Get CP nr. 'which'
    virtual void set_CP(int which, const npoint& pt);    ← Set CP nr. 'which'
    void translate(npoint vec);
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;    ← Get the maximum u (read-only)
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;    ← Get point on curve
                                                    of parameter u_
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);    ← Get CP nr. 'which'
    virtual void set_CP(int which, const npoint& pt);    ← Set CP nr. 'which'
    void translate(npoint vec);    ← Translate curve by vector 'vec'
    virtual double u(int which) const;
    virtual double& u(int which);
};
```

Class nlagrange

```
class nlagrange : public nparametriccurve
{
protected:
    std::vector<double> pos;    ← Parametric values of the control points
    std::vector<npoint> val;    ← Positions of the control points
    int nCP;    ← Number of control points
public:
    nlagrange(int nCP_);    ← Constructor
    virtual int degree(void) const;    ← Get the polynomial degree (read-only)
    virtual int nb_CP(void) const;    ← Get the number of control points (read-only)
    virtual void add_CP(double u_, const npoint &val_);    ← Add a CP
    virtual double min_u(void) const;    ← Get the minimum u (read-only)
    virtual double max_u(void) const;    ← Get the maximum u (read-only)
    double LagrangeBasis(int which, double u) const;
    virtual void P(double u_, npoint& ret) const;    ← Get point on curve
                                                    of parameter u_
    virtual npoint CP(int which) const;
    virtual npoint& CP(int which);    ← Get CP nr. 'which'
    virtual void set_CP(int which, const npoint& pt);    ← Set CP nr. 'which'
    void translate(npoint vec);    ← Translate curve by vector 'vec'
    virtual double u(int which) const;
    virtual double& u(int which);    ← Get parametric value 'which'
};
```

Class `npoint`: usage

- **Constructor**
 - `npoint p(0.0, 0.0, 0.0, 1.0);` // Euclidean point (0, 0, 0)
- **Get coordinates**
 - `double x = p[0];` // Get coordinate x
 - ...
 - `double w = p[3];` // Get coordinate w (always 1 for the moment)
- **Set coordinates**
 - `p[0] = x;` // Set coordinate x
 - ...
 - `p[3] = w;` // Set coordinate w

Class `nlagrange`: usage

- **Constructor**
 - `nlagrange curve(7);` // Create a lagrange curve with 7 CPs.
- **Get/Set parametric values**
 - `double u = curve.u(i);`
 - `curve.u(i) = ...;`
- **Get/Set control points**
 - `npoint cp = curve.CP(i);`
 - `npoint new_cp(..., ..., ..., 1); curve.set_CP(i, new_cp);`