3D Geometric Transformation

고려대학교 컴퓨터 그래픽스 연구실

Contents

CGVR

- Translation
- Scaling
- Rotation
- Rotations with Quaternions
- Other Transformations
- Coordinate Transformations

Transformation in 3D

CGVR

- Transformation Matrix

$$\begin{bmatrix} A & D & G & J \\ B & E & H & K \\ C & F & I & L \\ 0 & 0 & 0 & S \end{bmatrix} \Rightarrow \left[\begin{array}{c|c} 3\times 3 & 3\times 1 \\ \hline 1\times 3 & 1\times 1 \end{array}\right]$$

3×3 : Scaling, Reflection, Shearing, Rotation

3×1 : Translation

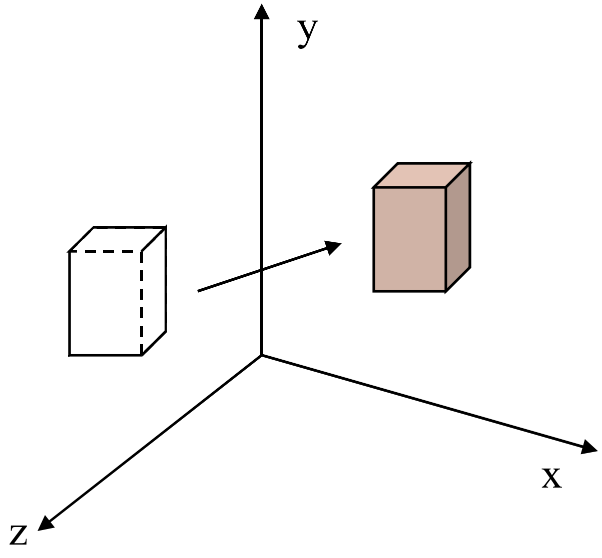
1×1 : Uniform global Scaling

1×3 : Homogeneous representation

3D Translation

- Translation of a Point

$$x' = x + t_x, \quad y' = y + t_y, \quad z' = z + t_z$$



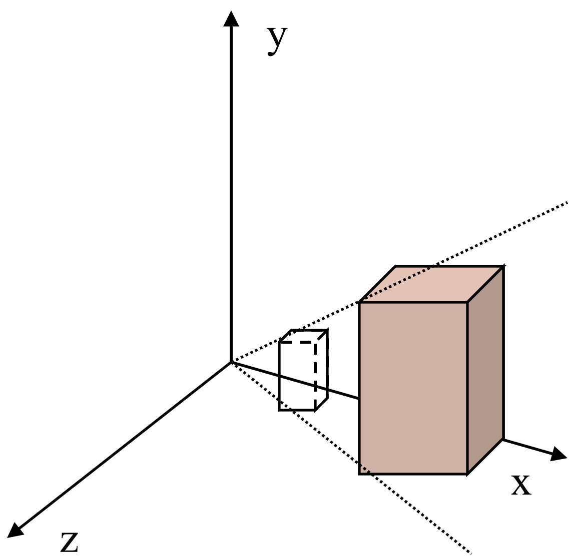
$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & t_x \\ 0 & 1 & 0 & t_y \\ 0 & 0 & 1 & t_z \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$

3D Scaling

CGVR

- Uniform Scaling

$$x' = x \cdot s_x\,, \quad y' = y \cdot s_y\,, \quad z' = z \cdot s_z$$

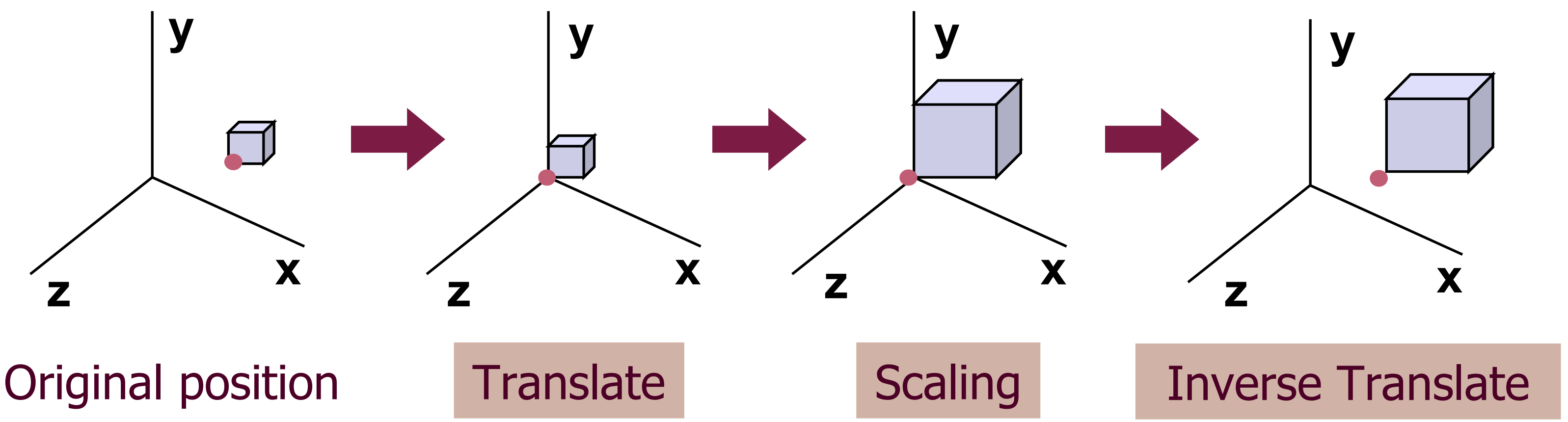


$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} s_x & 0 & 0 & 0 \\ 0 & s_y & 0 & 0 \\ 0 & 0 & s_z & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$

Relative Scaling

CGVR

- Scaling with a Selected Fixed Position



$$T(x_f,y_f,z_f)\cdot S(s_x,s_y,s_z)\cdot T(-x_f,-y_f,-z_f)=\begin{bmatrix}x'\\y'\\z'\\1\end{bmatrix}=\begin{bmatrix}1&0&0&x_f\\0&1&0&y_f\\0&0&1&z_f\\0&0&0&1\end{bmatrix}\begin{bmatrix}s_x&0&0&0\\0&s_y&0&0\\0&0&s_z&0\\0&0&0&1\end{bmatrix}\begin{bmatrix}1&0&0&-x_f\\0&1&0&-y_f\\0&0&1&-z_f\\0&0&0&1\end{bmatrix}\begin{bmatrix}x\\y\\z\\1\end{bmatrix}$$

3D Rotation

CGVR

- Coordinate-Axes Rotations
  - X-axis rotation
  - Y-axis rotation
  - Z-axis rotation

- General 3D Rotations
  - Rotation about an axis that is parallel to one of the coordinate axes
  - Rotation about an arbitrary axis

Coordinate-Axes Rotations

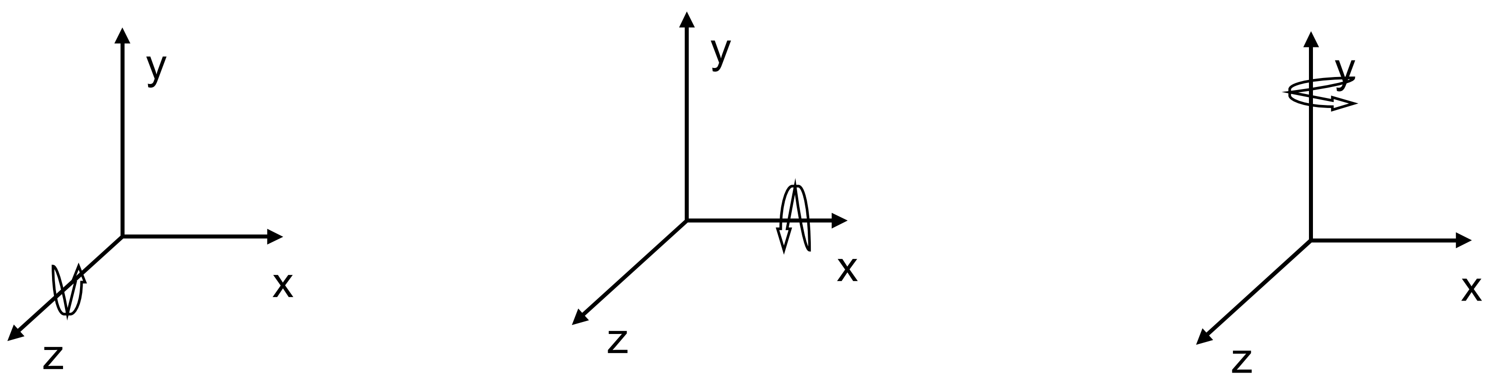
CGVR

- Z-Axis Rotation
- X-Axis Rotation
- Y-Axis Rotation

$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta & 0 & 0 \\ \sin\theta & \cos\theta & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$

$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \cos\theta & -\sin\theta & 0 \\ 0 & \sin\theta & \cos\theta & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$

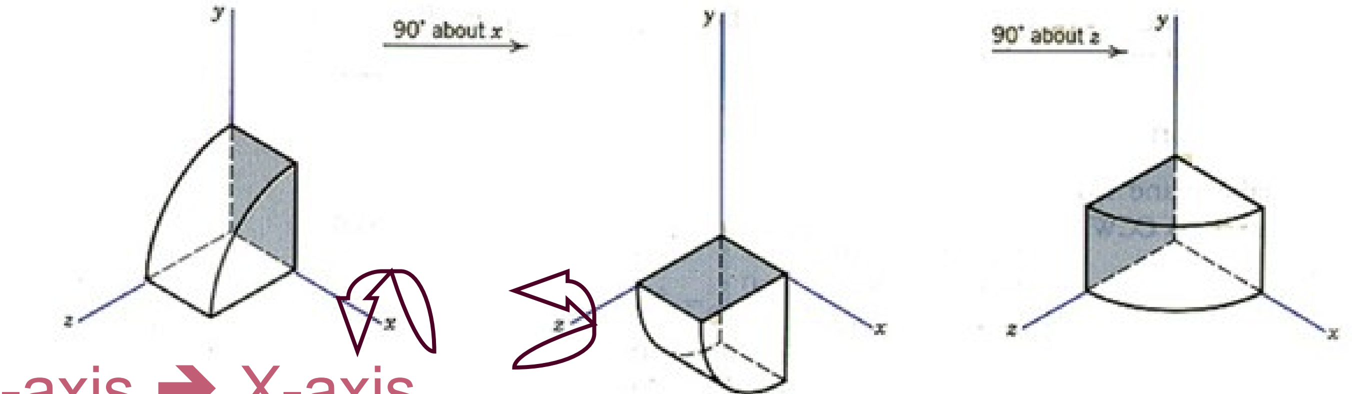
$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} \cos\theta & 0 & \sin\theta & 0 \\ 0 & 1 & 0 & 0 \\ -\sin\theta & 0 & \cos\theta & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$



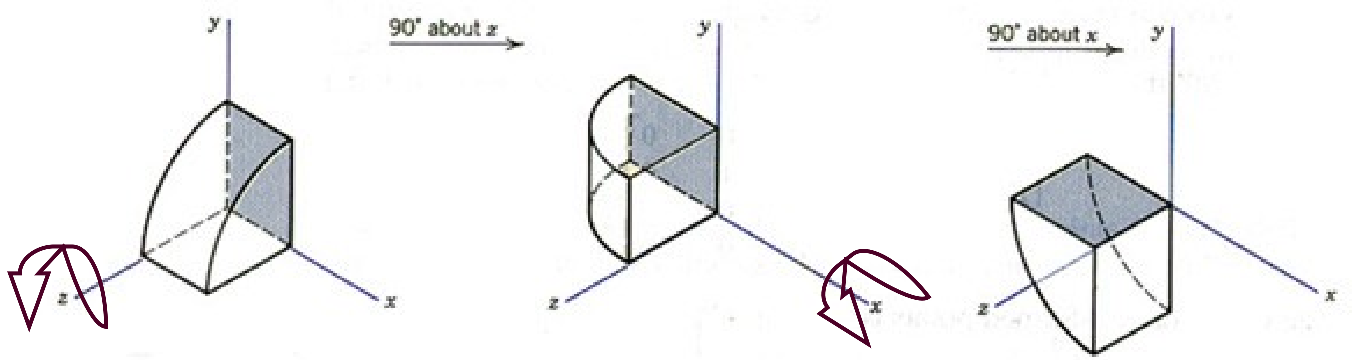
Order of Rotations

CGVR

- Order of Rotation Affects Final Position
  - X-axis → Z-axis



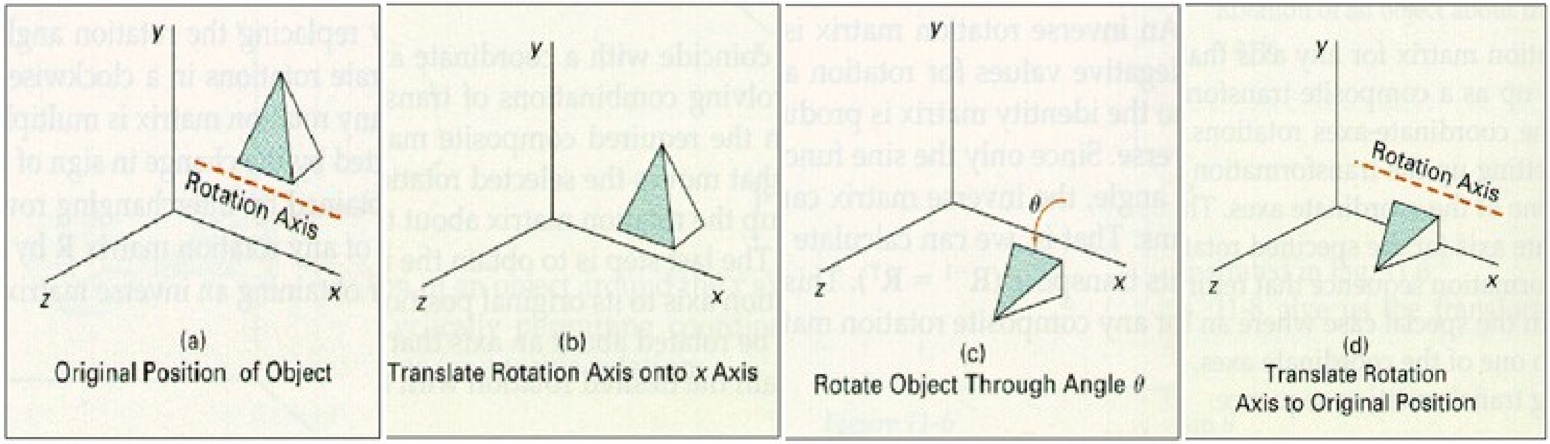
  - Z-axis → X-axis



General 3D Rotations

CGVR

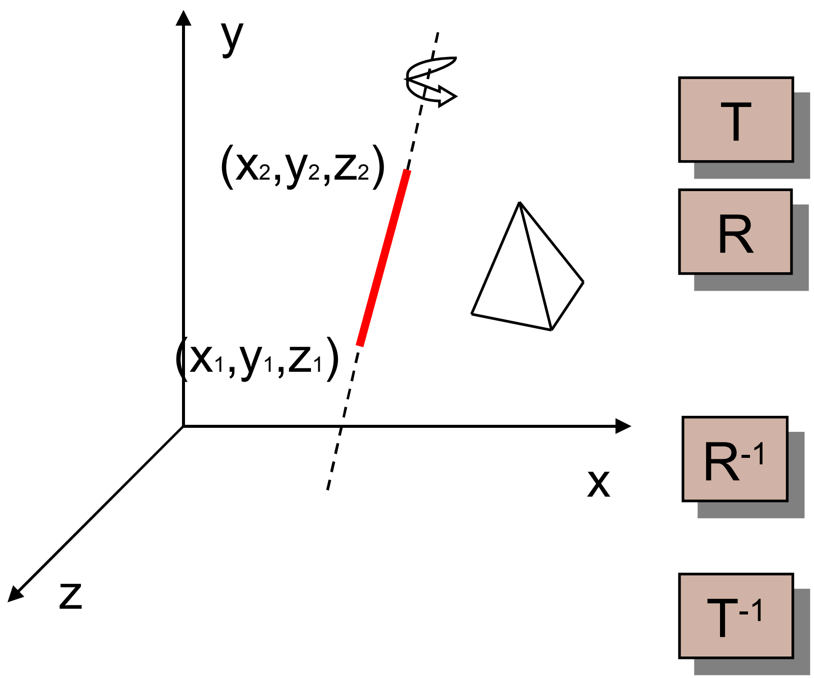
- Rotation about an Axis that is Parallel to One of the Coordinate Axes
  - **Translate** the object so that the rotation axis coincides with the parallel coordinate axis
  - Perform the specified **rotation** about that axis
  - **Translate** the object so that the rotation axis is moved back to its original position



(a) Original Position of Object
(b) Translate Rotation Axis onto x Axis
(c) Rotate Object Through Angle θ
(d) Translate Rotation Axis to Original Position

General 3D Rotations

- Rotation about an Arbitrary Axis



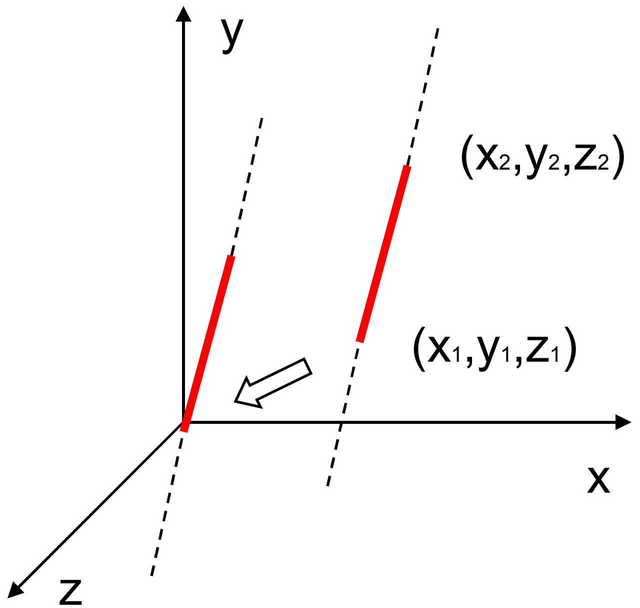
Basic Idea

3. **Translate (x1, y1, z1) to the origin**
4. **Rotate (x'2, y'2, z'2) on to the z axis**
5. **Rotate the object around the z-axis**
6. **Rotate the axis to the original orientation**
7. **Translate the rotation axis to the original position**

$$\mathbf{R}(\theta) = \mathbf{T}^{-1}\mathbf{R}_x^{-1}(\alpha)\mathbf{R}_y^{-1}(\beta)\mathbf{R}_z(\theta)\mathbf{R}_y(\beta)\mathbf{R}_x(\alpha)\mathbf{T}$$

General 3D Rotations

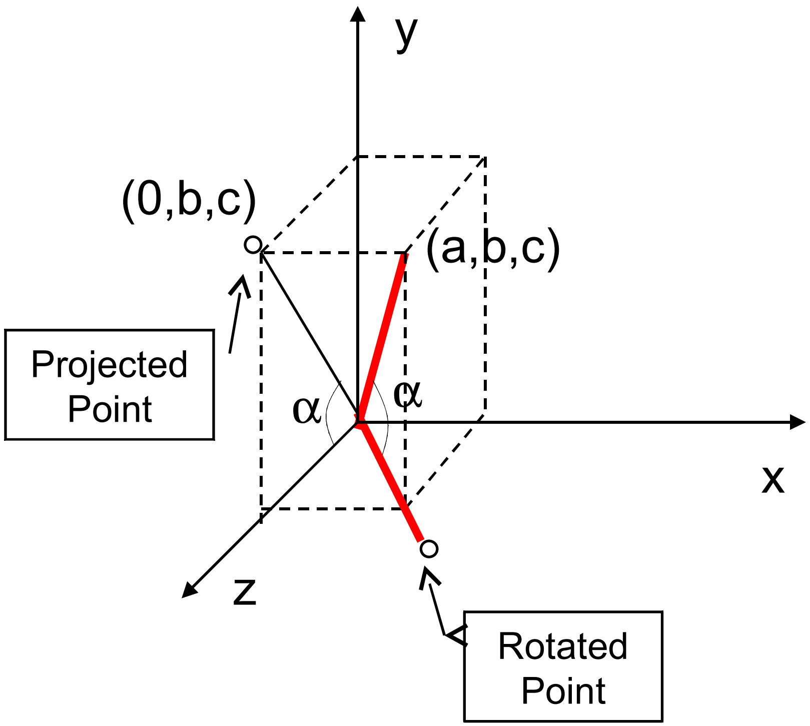
- Step 1. Translation



$$\mathbf{T} = \begin{bmatrix} 1 & 0 & 0 & -x_1 \\ 0 & 1 & 0 & -y_1 \\ 0 & 0 & 1 & -z_1 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

General 3D Rotations

- Step 2. Establish $[\ T_R\ ]^{\alpha}_{x}$ x axis



$$\sin\alpha = \frac{b}{\sqrt{b^2+c^2}} = \frac{b}{d}$$

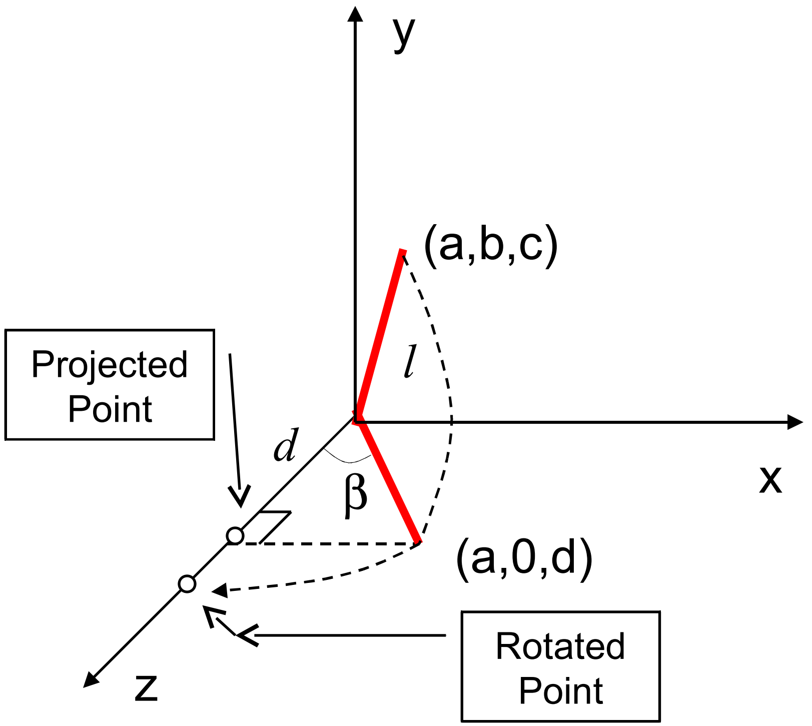
$$\cos\alpha = \frac{c}{\sqrt{b^2+c^2}} = \frac{c}{d}$$

$$\mathbf{R}_x(\alpha) = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \cos\alpha & -\sin\alpha & 0 \\ 0 & \sin\alpha & \cos\alpha & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & c/d & -b/d & 0 \\ 0 & b/d & c/d & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Arbitrary Axis Rotation

CGVR

- Step 3. Rotate about *y* axis by ϕ



$$\sin\beta = \frac{a}{l}, \qquad \cos\beta = \frac{d}{l}$$

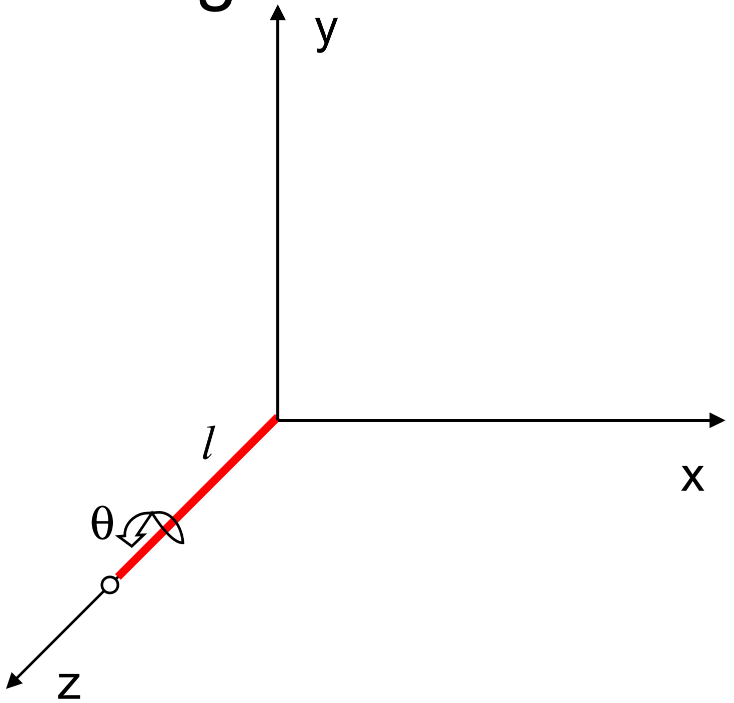
$$l^2 = a^2 + b^2 + c^2 = a^2 + d^2$$

$$d = \sqrt{b^2 + c^2}$$

$$\mathbf{R}_y(\beta) = \begin{bmatrix} \cos\beta & 0 & -\sin\beta & 0 \\ 0 & 1 & 0 & 0 \\ \sin\beta & 0 & \cos\beta & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} d/l & 0 & -a/l & 0 \\ 0 & 1 & 0 & 0 \\ a/l & 0 & d/l & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Arbitrary Axis Rotation

- Step 4. Rotate about *z* axis by the desired angle **θ**

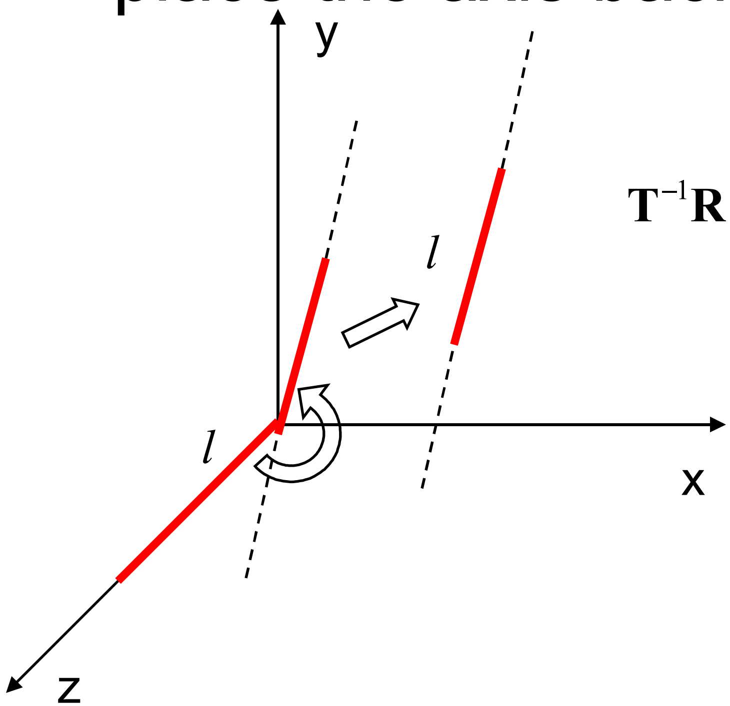


$$\mathbf{R}_z(\theta) = \begin{bmatrix} \cos\theta & -\sin\theta & 0 & 0 \\ \sin\theta & \cos\theta & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Arbitrary Axis Rotation

CGVR

- Step 5. Apply the reverse transformation to place the axis back in its initial position

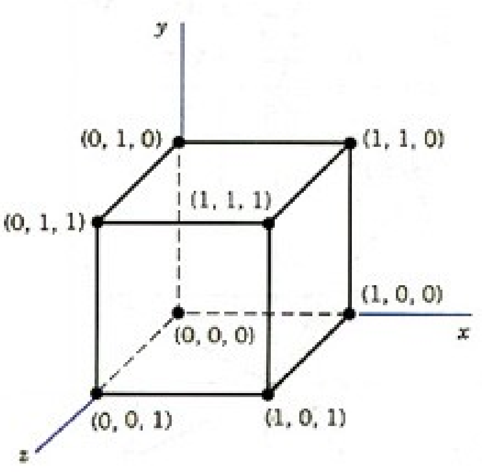


$$\mathbf{T}^{-1}\mathbf{R}_x^{-1}(\alpha)\mathbf{R}_y^{-1}(\beta) = \begin{bmatrix} 1 & 0 & 0 & -x_1 \\ 0 & 1 & 0 & -y_1 \\ 0 & 0 & 1 & -z_1 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \cos\alpha & \sin\alpha & 0 \\ 0 & -\sin\alpha & \cos\alpha & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \cos\beta & 0 & \sin\beta & 0 \\ 0 & 1 & 0 & 0 \\ -\sin\beta & 0 & \cos\beta & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$\mathbf{R}(\theta) = \mathbf{T}^{-1}\mathbf{R}_x^{-1}(\alpha)\mathbf{R}_y^{-1}(\beta)\mathbf{R}_z(\theta)\mathbf{R}_y(\beta)\mathbf{R}_x(\alpha)\mathbf{T}$$

Example

Find the new coordinates of a unit cube 90º-rotated about an axis defined by its endpoints A(2,1,0) and B(3,3,1).

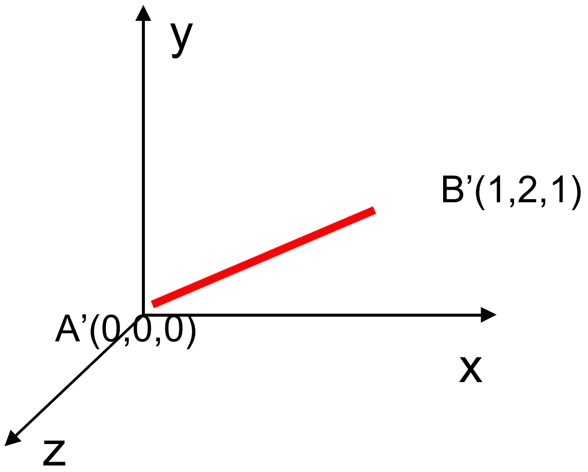


A Unit Cube

Example

CGVR

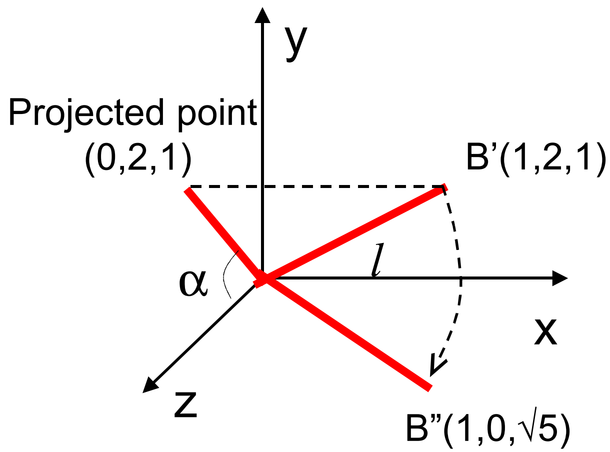
- Step1. Translate point A to the origin



$$\mathbf{T} = \begin{bmatrix} 1 & 0 & 0 & -2 \\ 0 & 1 & 0 & -1 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Example

- Step 2. Rotate axis *A'B'* about the x axis by and angle α, until it lies on the *xz* plane.



$$\sin\alpha = \frac{2}{\sqrt{2^2+1^2}} = \frac{2}{\sqrt{5}} = \frac{2\sqrt{5}}{5}$$

$$\cos\alpha = \frac{1}{\sqrt{5}} = \frac{\sqrt{5}}{5}$$

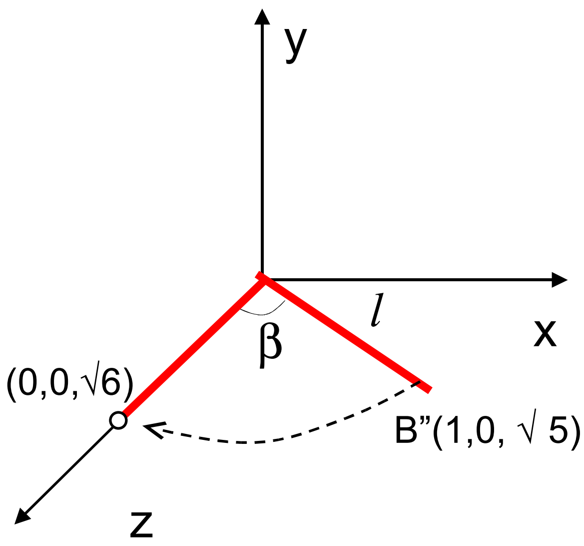
$$l = \sqrt{1^2+2^2+1^2} = \sqrt{6}$$

$$\mathbf{R}_x(\alpha) = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \frac{\sqrt{5}}{5} & -\frac{2\sqrt{5}}{5} & 0 \\ 0 & \frac{2\sqrt{5}}{5} & \frac{\sqrt{5}}{5} & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Example

CGVR

- Step 3. Rotate axis *A'B''* about the y axis by and angle ϕ, until it coincides with the z axis.



$$\sin\beta = \frac{1}{\sqrt{6}} = \frac{\sqrt{6}}{6}$$

$$\cos\beta = \frac{\sqrt{5}}{\sqrt{6}} = \frac{\sqrt{30}}{6}$$

$$\mathbf{R}_y(\beta) = \begin{bmatrix} \frac{\sqrt{30}}{6} & 0 & -\frac{\sqrt{6}}{6} & 0 \\ 0 & 1 & 0 & 0 \\ \frac{\sqrt{6}}{6} & 0 & \frac{\sqrt{30}}{6} & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Example

CGVR

- Step 4. Rotate the cube 90° about the z axis

$$\mathbf{R}_z(90°) = \begin{bmatrix} 0 & -1 & 0 & 0 \\ 1 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

  - Finally, the concatenated rotation matrix about the arbitrary axis AB becomes,

$$\mathbf{R}(\theta) = \mathbf{T}^{-1}\mathbf{R}_x^{-1}(\alpha)\mathbf{R}_y^{-1}(\beta)\mathbf{R}_z(90°)\mathbf{R}_y(\beta)\mathbf{R}_x(\alpha)\mathbf{T}$$

Example

CGVR

$$\mathbf{R}(\theta)=\begin{bmatrix}1&0&0&2\\0&1&0&1\\0&0&1&0\\0&0&0&1\end{bmatrix}\begin{bmatrix}1&0&0&0\\0&\frac{\sqrt{5}}{5}&\frac{2\sqrt{5}}{5}&0\\0&-\frac{2\sqrt{5}}{5}&\frac{\sqrt{5}}{5}&0\\0&0&0&1\end{bmatrix}\begin{bmatrix}\frac{\sqrt{30}}{6}&0&\frac{\sqrt{6}}{6}&0\\0&1&0&0\\-\frac{\sqrt{6}}{6}&0&\frac{\sqrt{30}}{6}&0\\0&0&0&1\end{bmatrix}\begin{bmatrix}0&-1&0&0\\1&0&0&0\\0&0&1&0\\0&0&0&1\end{bmatrix}$$

$$\begin{bmatrix}\frac{\sqrt{30}}{6}&0&-\frac{\sqrt{6}}{6}&0\\0&1&0&0\\\frac{\sqrt{6}}{6}&0&\frac{\sqrt{30}}{6}&0\\0&0&0&1\end{bmatrix}\begin{bmatrix}1&0&0&0\\0&\frac{\sqrt{5}}{5}&-\frac{2\sqrt{5}}{5}&0\\0&\frac{2\sqrt{5}}{5}&\frac{\sqrt{5}}{5}&0\\0&0&0&1\end{bmatrix}\begin{bmatrix}1&0&0&-2\\0&1&0&-1\\0&0&1&0\\0&0&0&1\end{bmatrix}$$

$$=\begin{bmatrix}0.166&-0.075&0.983&1.742\\0.742&0.667&0.075&-1.151\\-0.650&0.741&0.167&0.560\\0&0&0&1\end{bmatrix}$$

Example

CGVR

- Multiplying $\mathbf{R}(\theta)$ by the point matrix of the original cube

$$\left[\mathbf{P}'\right] = \mathbf{R}\left(\theta\right) \cdot \left[\mathbf{P}\right]$$

$$\left[\mathbf{P}'\right] = \begin{bmatrix} 0.166 & -0.075 & 0.983 & 1.742 \\ 0.742 & 0.667 & 0.075 & -1.151 \\ -0.650 & 0.741 & 0.167 & 0.560 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 0 & 0 & 1 & 1 & 0 & 0 & 1 & 1 \\ 1 & 1 & 1 & 1 & 0 & 0 & 0 & 0 \\ 1 & 0 & 0 & 1 & 1 & 0 & 0 & 1 \\ 1 & 1 & 1 & 1 & 1 & 1 & 1 & 1 \end{bmatrix}$$

$$= \begin{bmatrix} 2.650 & 1.667 & 1.834 & 2.816 & 2.725 & 1.742 & 1.909 & 2.891 \\ -0.558 & -0.484 & 0.258 & 0.184 & -1.225 & -1.151 & -0.409 & -0.483 \\ 1.467 & 1.301 & 0.650 & 0.817 & 0.726 & 0.560 & -0.091 & 0.076 \\ 1 & 1 & 1 & 1 & 1 & 1 & 1 & 1 \end{bmatrix}$$

Rotations with Quaternions

CGVR

- Quaternion
  - Scalar part s + vector part $\mathbf{v}$ = (a, b, c)
  - Real part + complex part (imaginary numbers i, j, k)

$$q = (s,\ \mathbf{v}) = s + ai + bj + ck$$

- Rotation about any axis
  - Set up a unit quaternion ($\mathbf{u}$: unit vector)

$$s = \cos\frac{\theta}{2},\quad \mathbf{v} = \mathbf{u}\sin\frac{\theta}{2}$$

  - Represent any point position $\mathbf{P}$ in quaternion notation ($\mathbf{p}$ = (x, y, z))

$$\mathbf{P} = (0,\ \mathbf{p})$$

Rotations with Quaternions

CGVR

- Carry out with the quaternion operation ($q^{-1}=(s, -\mathbf{v})$)

$$\mathbf{P}' = q\mathbf{P}q^{-1}$$

- Produce the new quaternion

$$\mathbf{P}' = (0,\ \mathbf{p}')$$

$$\mathbf{p}' = s^2\mathbf{p} + \mathbf{v}(\mathbf{p}\cdot\mathbf{v}) + 2s(\mathbf{v}\times\mathbf{p}) + \mathbf{v}\times(\mathbf{v}\times\mathbf{p})$$

- Obtain the rotation matrix by quaternion multiplication

$$\mathbf{M}_R(\theta) = \mathbf{R}_x^{-1}(\alpha)\mathbf{R}_y^{-1}(\beta)\mathbf{R}_z(\theta)\mathbf{R}_y(\beta)\mathbf{R}_x(\alpha)$$

$$= \begin{bmatrix} 1-2b^2-2c^2 & 2ab-2sc & 2ac+2sb \\ 2ab+2sc & 1-2a^2-2c^2 & 2bc-2sa \\ 2ac-2sb & 2bc+2sa & 1-2a^2-2b^2 \end{bmatrix}$$

- Include the translations: $\mathbf{R}(\theta) = \mathbf{T}^{-1}\mathbf{M}_R(\theta)\mathbf{T}$

Example

CGVR

- Rotation about z axis
  - Set the unit quaternion: $s = \cos\frac{\theta}{2}, \ \mathbf{v} = (0, \ 0, \ 1)\sin\frac{\theta}{2}$
  - Substitute $a=b=0$, $c=\sin(\theta/2)$ into the matrix:

$$\mathbf{M}_R(\theta) = \begin{bmatrix} 1-2\sin^2\frac{\theta}{2} & -2\cos\frac{\theta}{2}\sin\frac{\theta}{2} & 0 \\ 2\cos\frac{\theta}{2}\sin\frac{\theta}{2} & 1-2\sin^2\frac{\theta}{2} & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

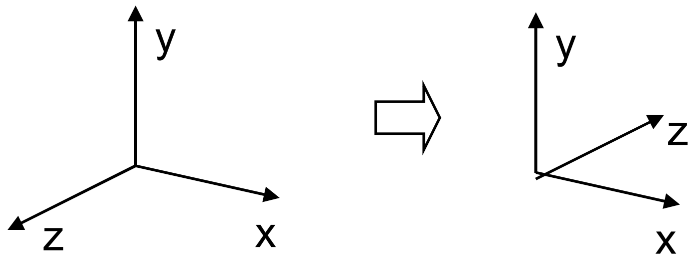
$$= \begin{bmatrix} \cos\theta & -\sin\theta & 0 \\ \sin\theta & \cos\theta & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$1-2\sin^2\frac{\theta}{2} = \cos\theta$$

$$2\cos\frac{\theta}{2}\sin\frac{\theta}{2} = \sin\theta$$

Other Transformations

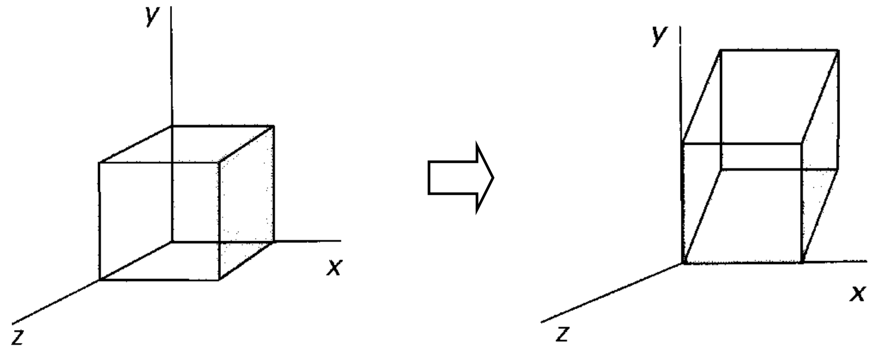
- Reflection Relative to the xy Plane



$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & -1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$

- Z-axis Shear

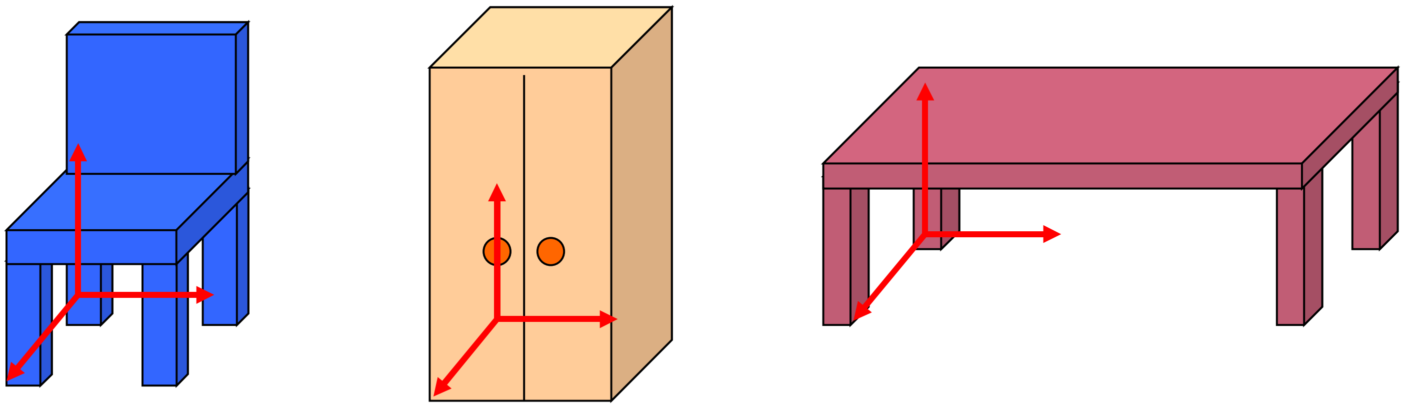
$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & a & 0 \\ 0 & 1 & b & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$



Coordinate Transformations

CGVR

- Multiple Coordinate System
  - Local (modeling) coordinate system
  - World coordinate scene

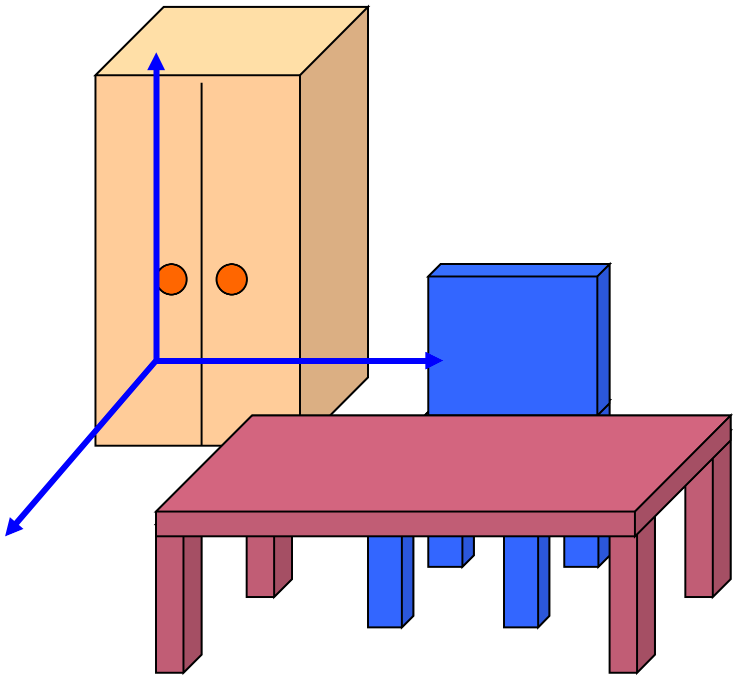


Local Coordinate System

Coordinate Transformations

CGVR

- Multiple Coordinate System
  - Local (modeling) coordinate system
  - World coordinate scene

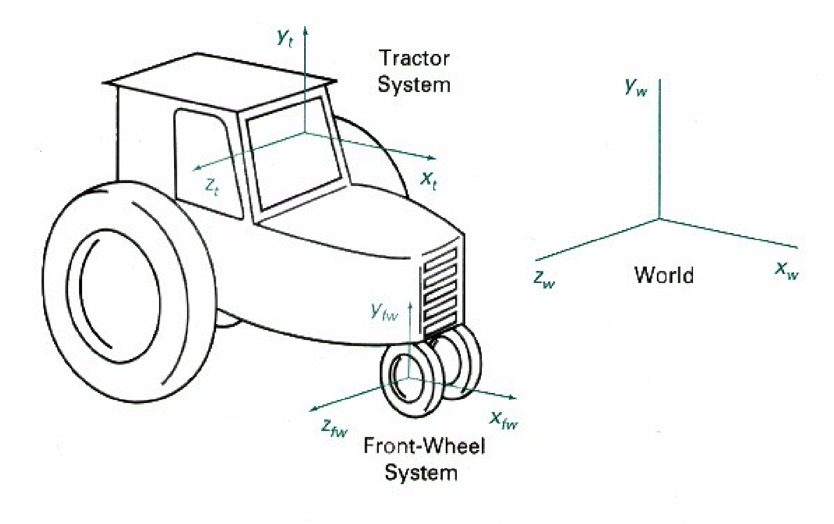


Word Coordinate System

Coordinate Transformations

CGVR

- Example – Simulation of Tractor movement
  - As tractor moves, **tractor coordinate system** and **front-wheel coordinate system** move in world coordinate system
  - **Front wheels** rotate in wheel coordinate system

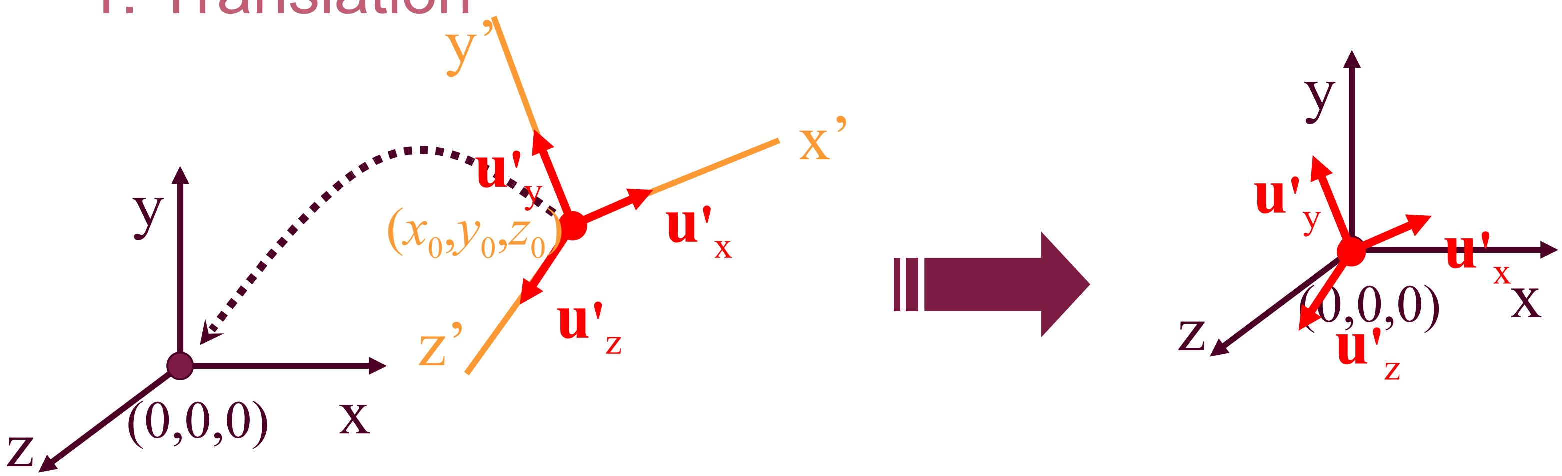


Coordinate Transformations

CGVR

- Transformation of an Object Description from One Coordinate System to Another
- Transformation Matrix
  - Bring the two coordinates systems into alignment

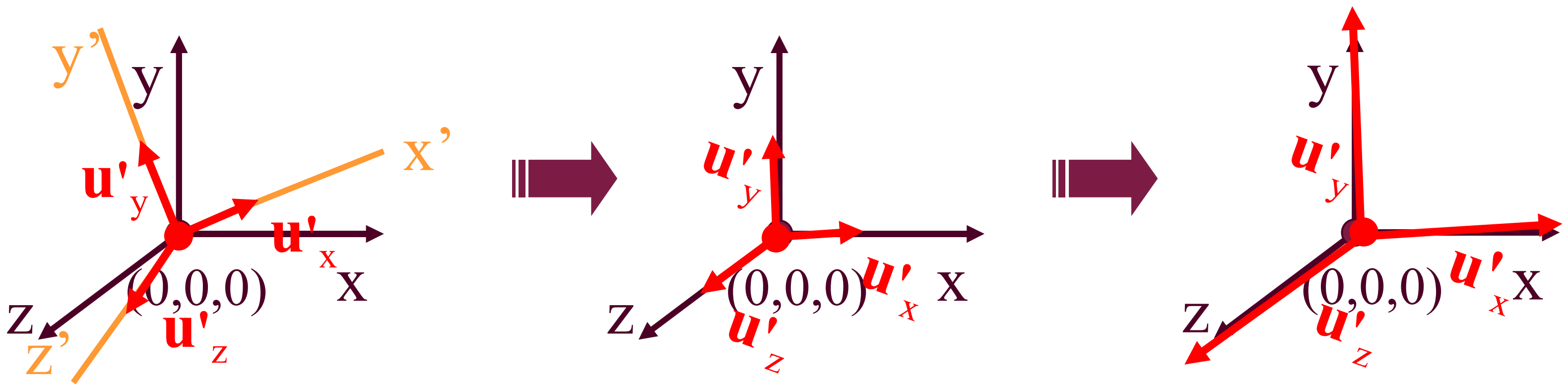
1. Translation



$$\mathbf{T}\left(-x_0,\ -y_0,\ -z_0\right)$$

Coordinate Transformations

2. Rotation & Scaling



$$\mathbf{R} = \begin{bmatrix} u'_{x_1} & u'_{x_2} & u'_{x_3} & 0 \\ u'_{y_1} & u'_{y_2} & u'_{y_3} & 0 \\ u'_{z_1} & u'_{z_2} & u'_{z_3} & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$