

## Lecture 20: Curves & Surfaces II

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# Outlines

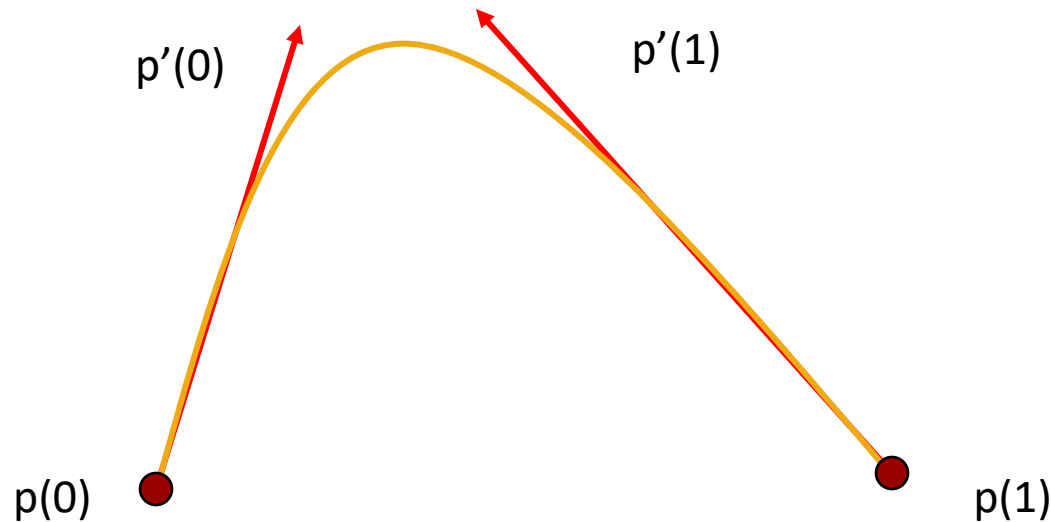
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- Curves and surfaces
  - Hermite
  - Bezier
  - Splines



# Hermite Form

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- Use two interpolating conditions and two derivative conditions per segment
- Ensures continuity and first derivative continuity between segments

# Hermite Form Equations

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Interpolating conditions are the same at ends

$$p(0) = p_0 = c_0$$

$$p(1) = p_3 = c_0 + c_1 + c_2 + c_3$$

Differentiating we find  $p'(u) = c_1 + 2uc_2 + 3u^2c_3$

Evaluating at end points

$$p'(0) = p'_0 = c_1$$

$$p'(1) = p'_3 = c_1 + 2c_2 + 3c_3$$



# Matrix Form

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- We find  $\mathbf{c} = \mathbf{M}_H \mathbf{q}$  where  $\mathbf{M}_H$  is the Hermite matrix

$$\mathbf{q} = \begin{bmatrix} p_0 \\ p_3 \\ p'_0 \\ p'_3 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 1 & 1 & 1 & 1 \\ 0 & 1 & 0 & 0 \\ 0 & 1 & 2 & 3 \end{bmatrix} \mathbf{c} \quad \Rightarrow \quad \mathbf{M}_H = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ -3 & 3 & -2 & -1 \\ 2 & -2 & 1 & 1 \end{bmatrix}$$

# Hermite Blending Polynomials

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$$p(u) = u^T \mathbf{M}_H \mathbf{q} = \mathbf{b}(u)^T \mathbf{q}$$

$$\mathbf{b}(u) = \begin{bmatrix} 2u^3 - 3u^2 + 1 \\ -2u^3 + 3u^2 \\ u^3 - 2u^2 + u \\ u^3 - u^2 \end{bmatrix}$$

No zeros in  $[0, 1]$ , much smoother than interpolation  
blending polynomials



# Hermite Blending Polynomial

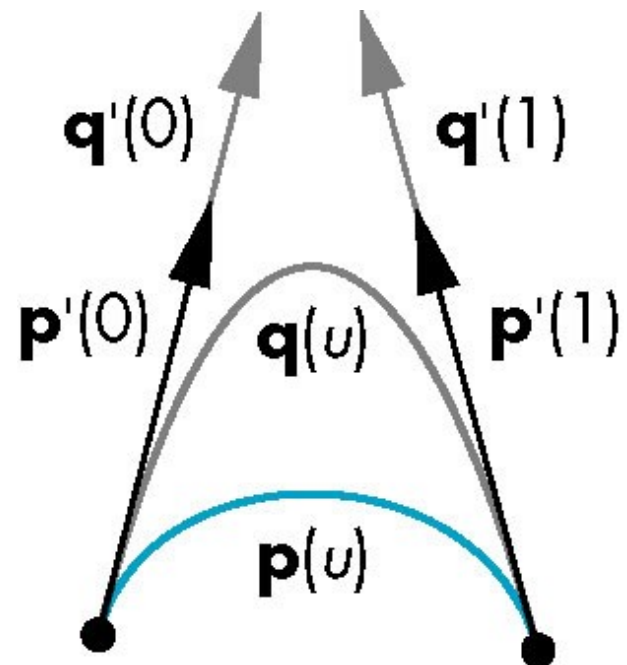
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- Although Hermit blending functions are smooth, it is not used directly in Computer Graphics and CAD because we usually have control points rather than derivatives
- However, the Hermite form is the basis of the Bezier form



# Hermite Form Example

- Here the  $p$  and  $q$  have the same tangents at the ends of the segment but different derivatives
- Generate different Hermite curves
- This techniques is used in drawing applications





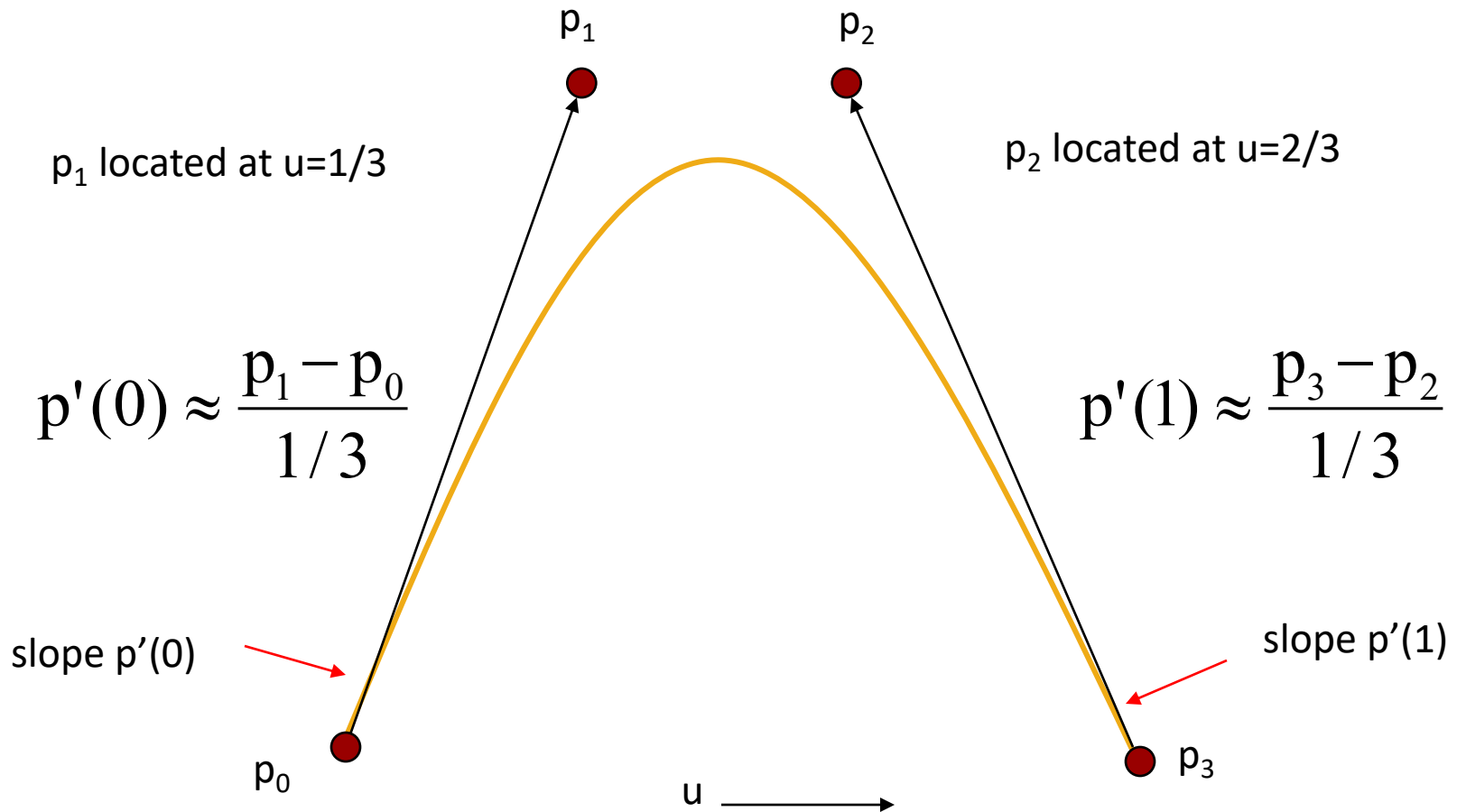
# Bézier's Idea

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- In graphics and CAD, we do not usually have derivative data
- Bezier suggested using the same 4 data points as with the cubic interpolating curve to approximate the derivatives in the Hermite form



# Approximating Derivatives



# Bézier Equations

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- Interpolating conditions are the same

$$p(0) = p_0 = c_0$$

$$p(1) = p_3 = c_0 + c_1 + c_2 + c_3$$

- Approximating derivative conditions

$$p'(0) = (p_1 - p_0) / (1/3) = c_0$$

$$p'(1) = (p_3 - p_2) / (1/3) = c_1 + 2c_2 + 3c_3$$

- Solve three linear systems of four equations and four unknowns for  $\mathbf{c} = \mathbf{M}_B \mathbf{p}$



# Bézier Matrix

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$$\mathbf{M}_B = \begin{bmatrix} 1 & 0 & 0 & 0 \\ -3 & 3 & 0 & 0 \\ 3 & -6 & 3 & 0 \\ -1 & 3 & -3 & 1 \end{bmatrix}$$

$$p(u) = \mathbf{u}^T \mathbf{c} = \mathbf{u}^T \mathbf{M}_B \mathbf{p} = \mathbf{b}(u)^T \mathbf{p}$$

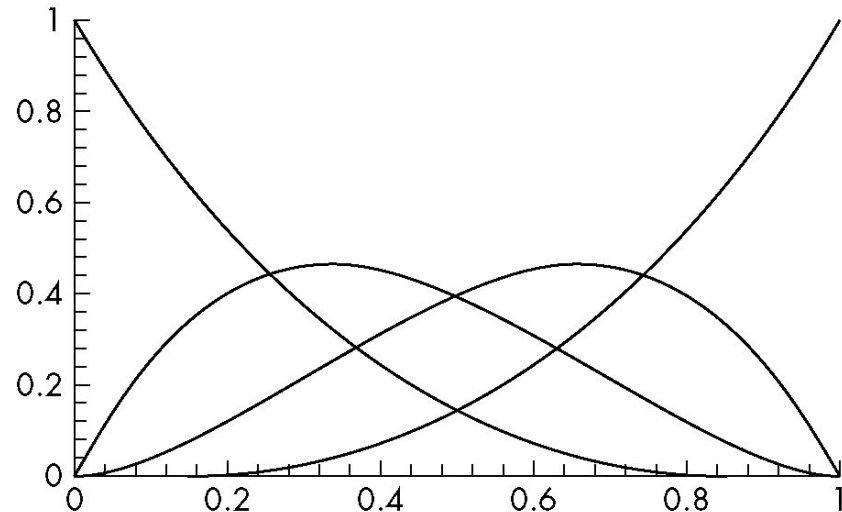
blending functions



# Bézier Blending Functions

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$$\mathbf{b}(u) = \begin{bmatrix} (1-u)^3 \\ 3u(1-u)^2 \\ 3u^2(1-u) \\ u^3 \end{bmatrix}$$



Note that all zeros are at 0 and 1 which forces the functions to be smooth over  $(0,1)$

# Bernstein Polynomials

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- The blending functions are a special case of the Bernstein polynomials

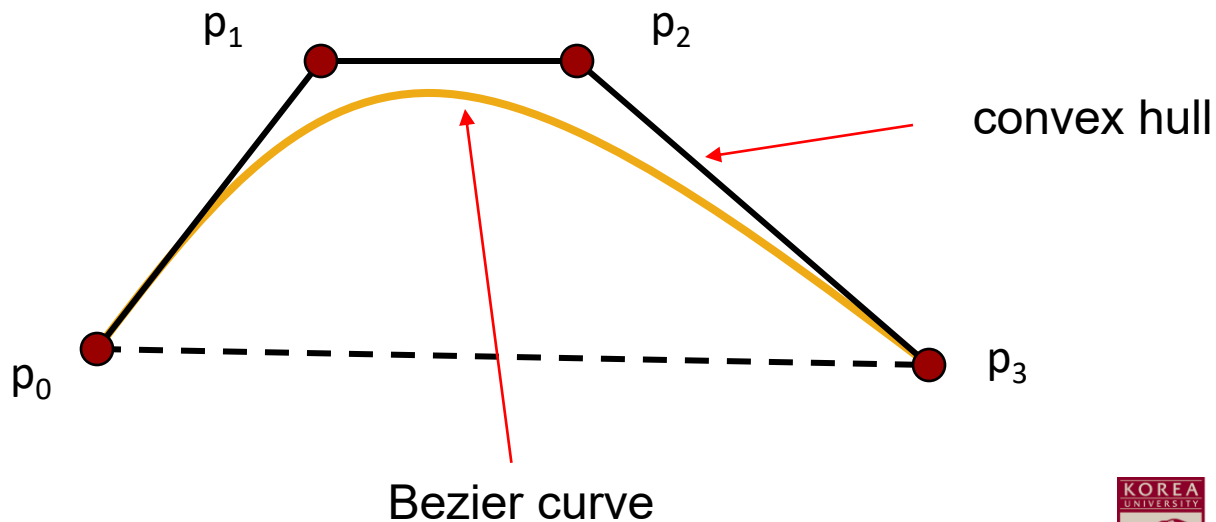
$$b_{kd}(u) = \frac{d!}{k!(d-k)!} u^k (1-u)^{d-k}$$

- These polynomials give the blending polynomials for any degree Bezier form
  - All zeros at 0 and 1
  - For any degree they all sum to 1 :  $\sum_{i=1}^d b_{id}(u) = 1$
  - They are all between 0 and 1 inside (0,1)



# Convex Hull Property

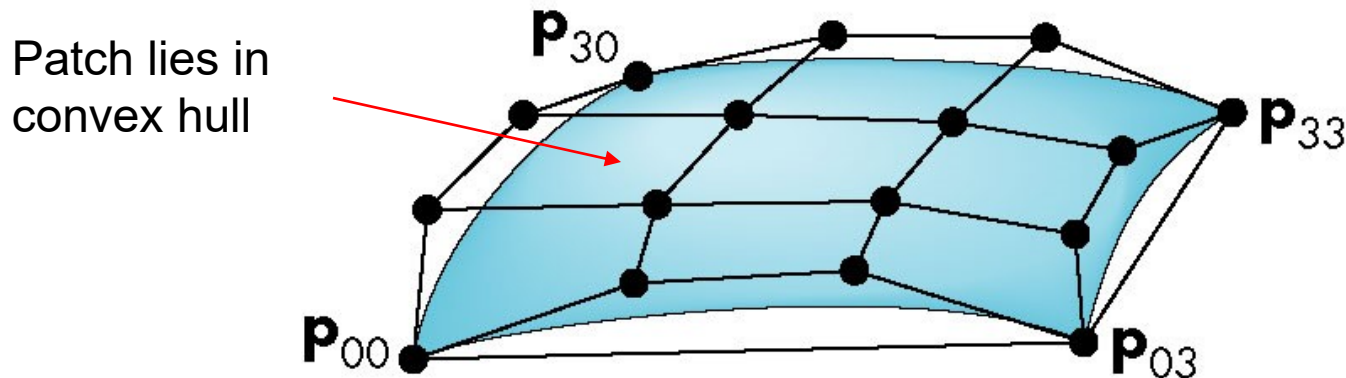
- The properties of the Bernstein polynomials ensure that all Bezier curves lie in the convex hull of their control points
- Hence, even though we do not interpolate all the data, we cannot be too far away



# Bézier Patches

- Using same data array  $\mathbf{P}=[p_{ij}]$  as with interpolating form, using bézier blending function

$$p(u, v) = \sum_{i=0}^3 \sum_{j=0}^3 b_i(u) b_j(v) p_{ij} = \mathbf{u}^T \mathbf{M}_B \mathbf{P} \mathbf{M}_B^T \mathbf{v}$$





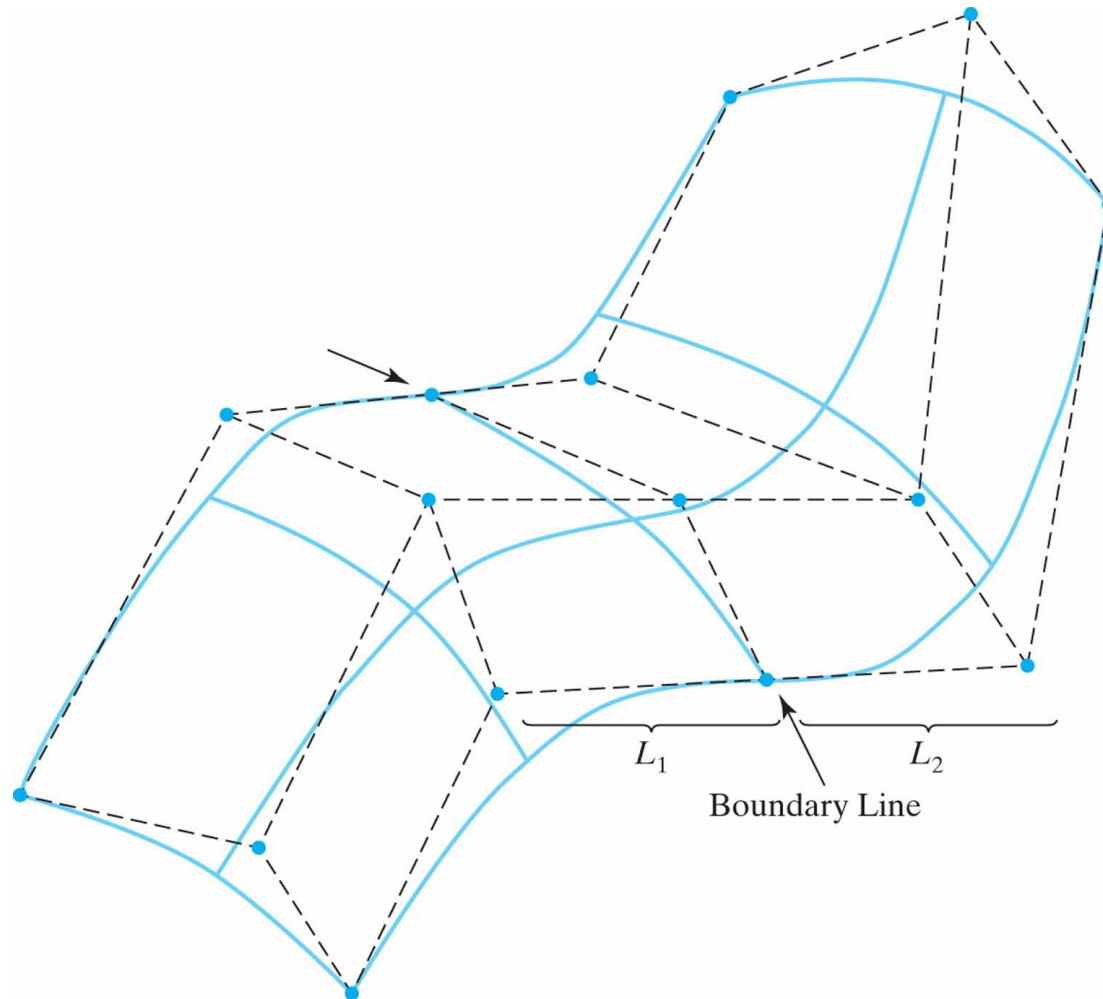
# Bézier Curve/Surface Analysis

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- Interpolating end points
- $C^0$  continuous at joint
- $C^1$  if end line segments are co-linear
- Increasing Bezier degree does not increase continuity at joint (why?)
  - Better to connect lower degree Bezier for local control



# Bézier Surface



# Splines

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- Approximating
- Smooth joint
  - $C^2$  continuous
- Compact support



# Cubic B-Spline

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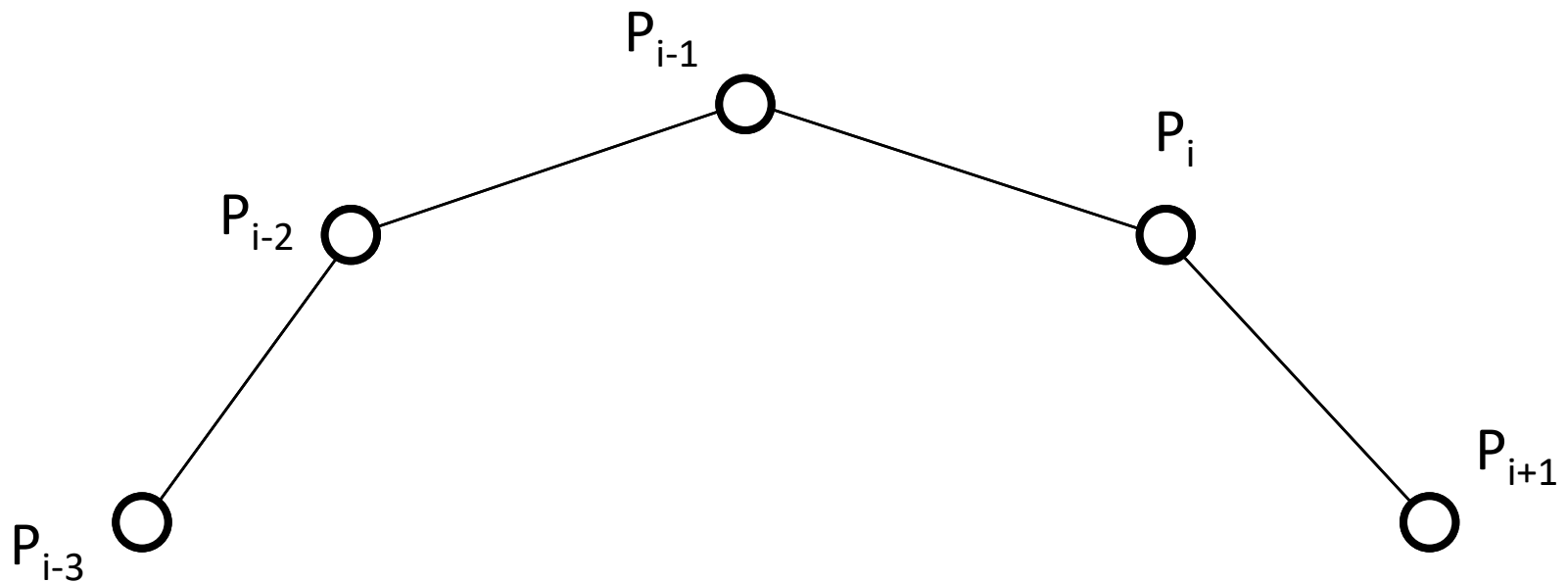
- Basis splines: use the data at  $\mathbf{p}=[p_{i-2} \ p_{i-1} \ p_i \ p_{i-1}]^T$  to define curve only between  $p_{i-1}$  and  $p_i$
- $C^2$  at interior points
- Cost is 3 times as much work for curves
  - For surfaces, we do 9 times as much work
- Add one new point each time rather than three as in Cubic Bézier



# Cubic B-Spline

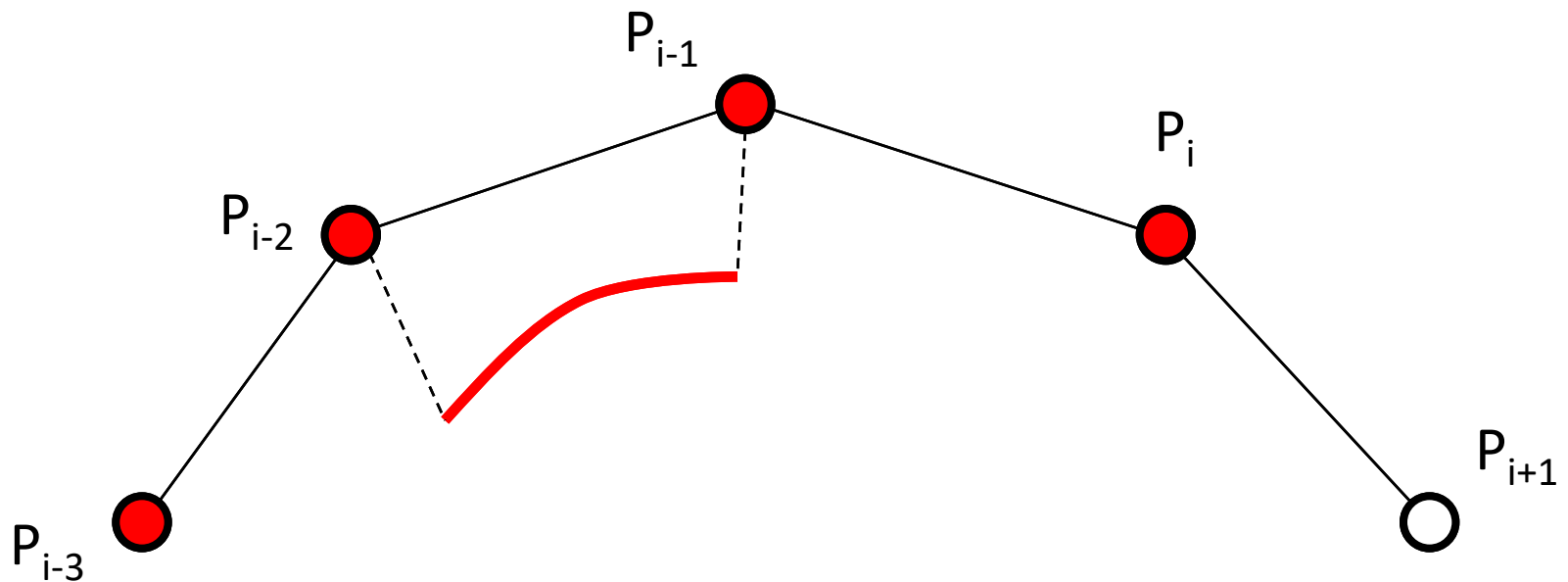
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- Four control points make a curve segment



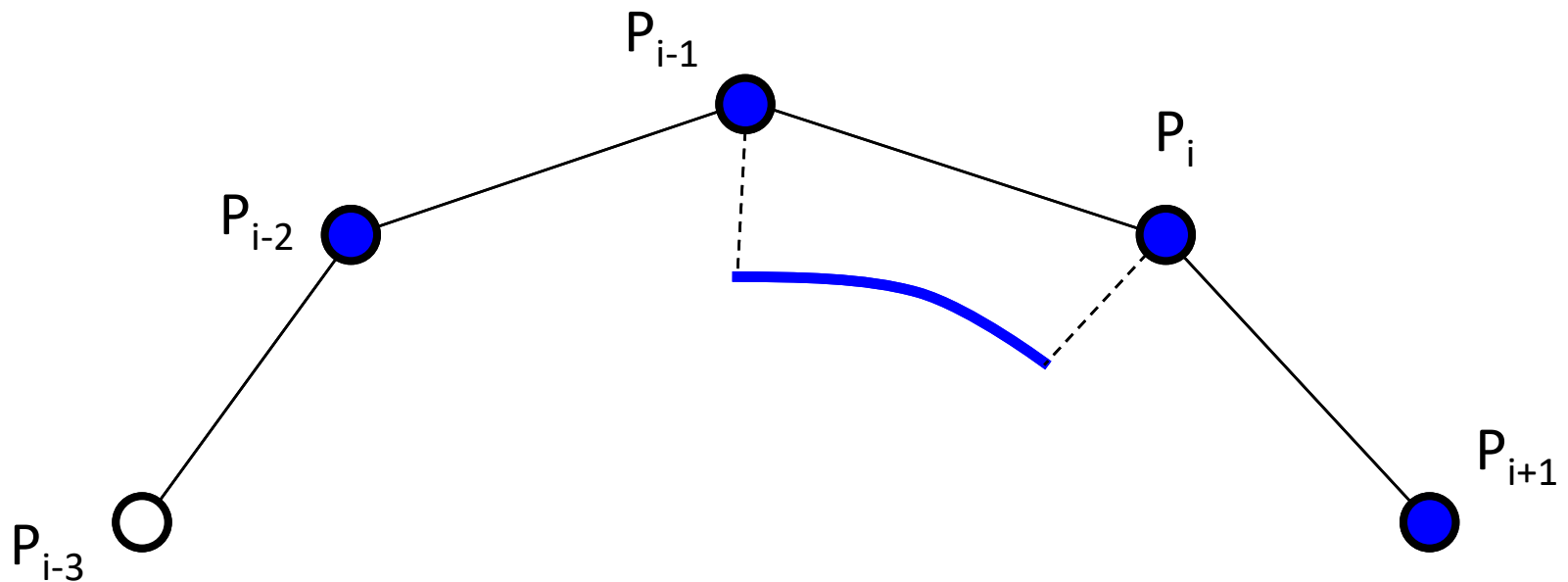
# Cubic B-Spline

- Four control points make a curve segment



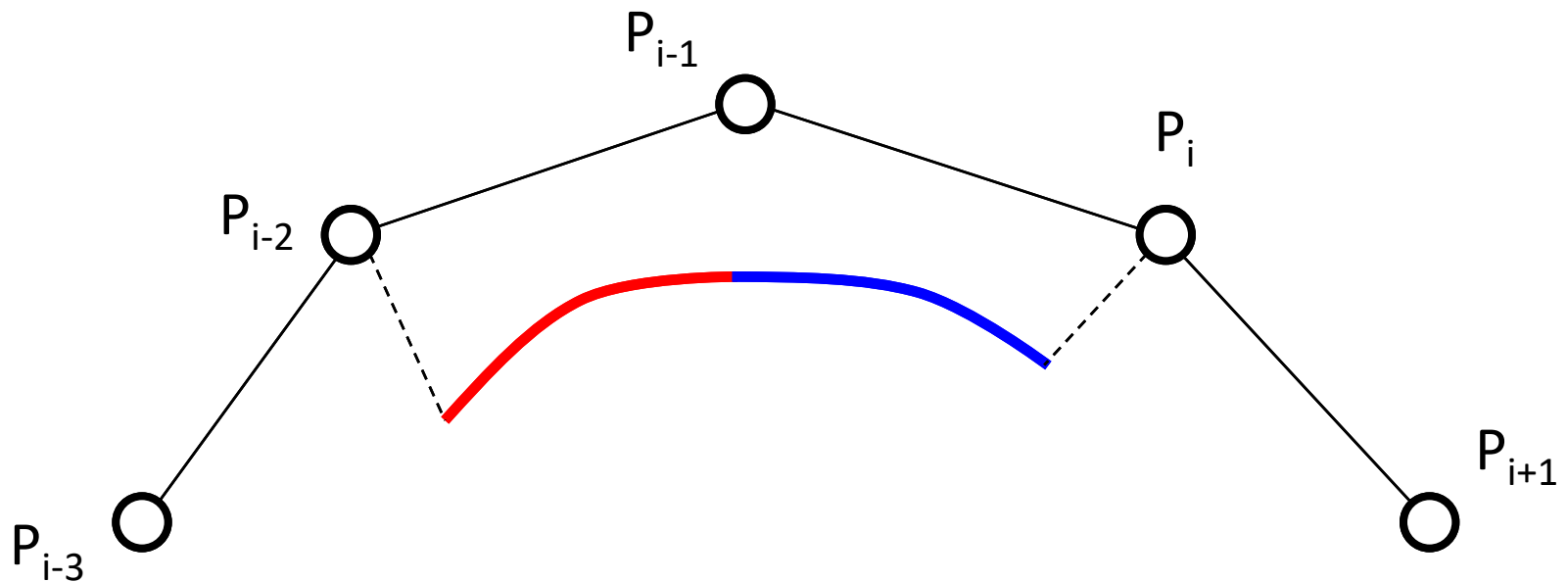
# Cubic B-Spline

- Four control points make a curve segment



# Cubic B-Spline

- Four control points make a curve segment





# Deriving Cubic B-spline

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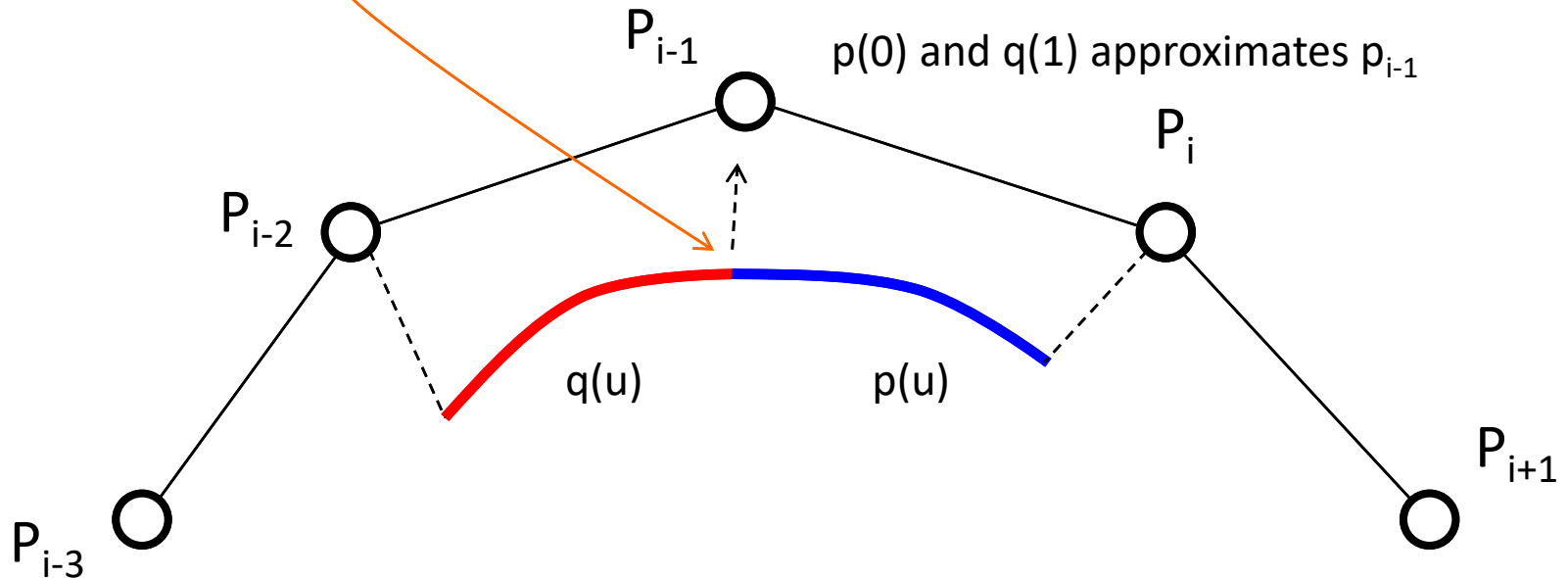
- Consider points
  - $p_{i-2}, p_{i-1}, p_i, p_{i+1}$  :  $p(0)$  approx  $p_{i-1}$ ,  $p(1)$  approx  $p_i$
  - $p_{i-3}, p_{i-2}, p_{i-1}, p_i$  :  $q(0)$  approx  $p_{i-2}$ ,  $q(1)$  approx  $p_{i-1}$
- Condition 1 :  $p(0)=q(1)$ 
  - Symmetry:  $p(0) = q(1) = 1/6(p_{i-2} + 4 p_{i-1} + p_i)$
- Condition 2 :  $p'(0)=q'(1)$ 
  - Geometry:  $p'(0) = q'(1) = 1/2 ((p_i - p_{i-1}) + (p_{i-1} - p_{i-2})) = 1/2 (p_i - p_{i-2})$



# End-point Constraints

$$q(1) = p(0) = \frac{1}{6}(p_{i-2} + 4p_{i-1} + p_i) = c_0 \quad p(u) = \sum_{k=0}^3 c_k u^k$$

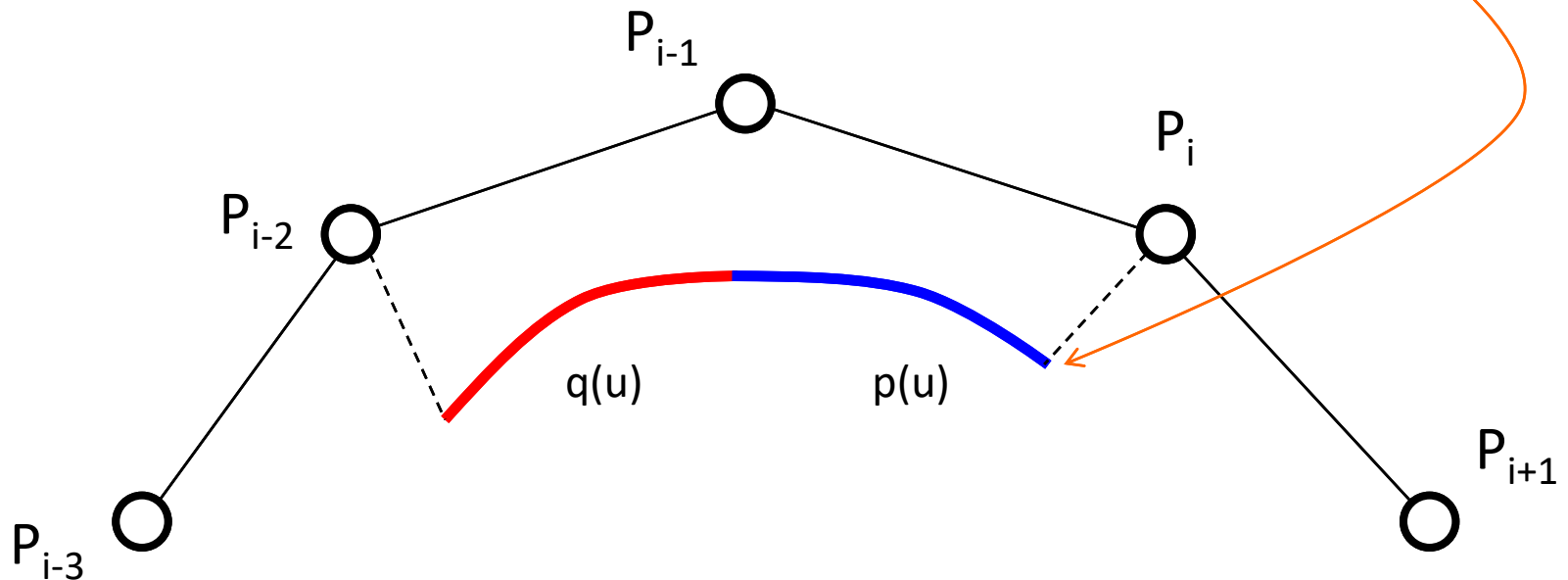
$$q'(1) = p'(0) = \frac{1}{2}(p_i - p_{i-2}) = c_1$$



# End-point Constraints

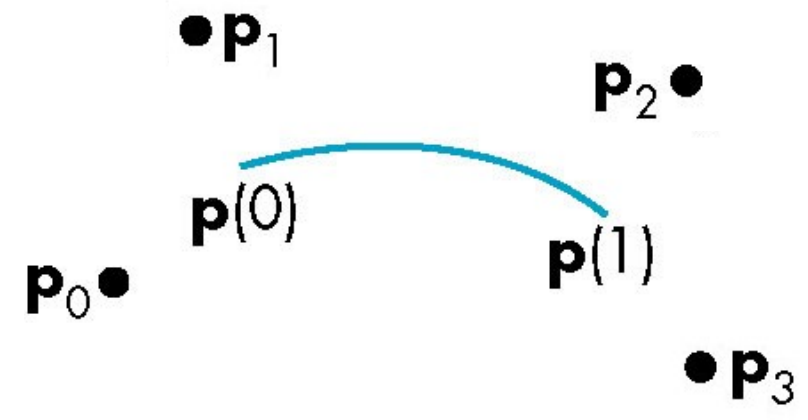
$$p(1) = \frac{1}{6}(p_{i-1} + 4p_i + p_{i+1}) = c_0 + c_1 + c_2 + c_3$$

$$p'(1) = \frac{1}{2}(p_{i+1} - p_{i-1}) = c_1 + 2c_2 + 3c_3$$



# Cubic B-spline

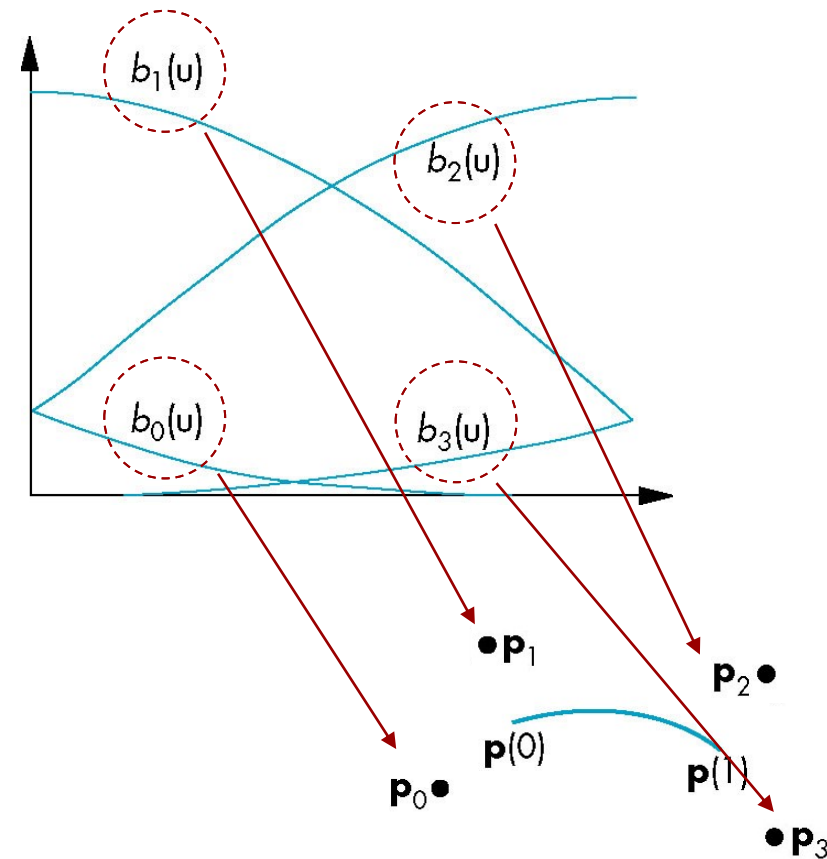
$$p(u) = \mathbf{u}^T \mathbf{c} = \mathbf{u}^T \mathbf{M}_s \mathbf{p} = \mathbf{b}(u)^T \mathbf{p}$$

$$\mathbf{M}_s = \begin{bmatrix} 1 & 4 & 1 & 0 \\ -3 & 0 & 3 & 0 \\ 3 & -6 & 3 & 0 \\ -1 & 3 & -3 & 1 \end{bmatrix}$$


# Blending Functions

$$\mathbf{b}(u) = \frac{1}{6} \begin{bmatrix} (1-u)^3 \\ 4-6u^2+3u^3 \\ 1+3u+3u^2-3u^3 \\ u^3 \end{bmatrix}$$

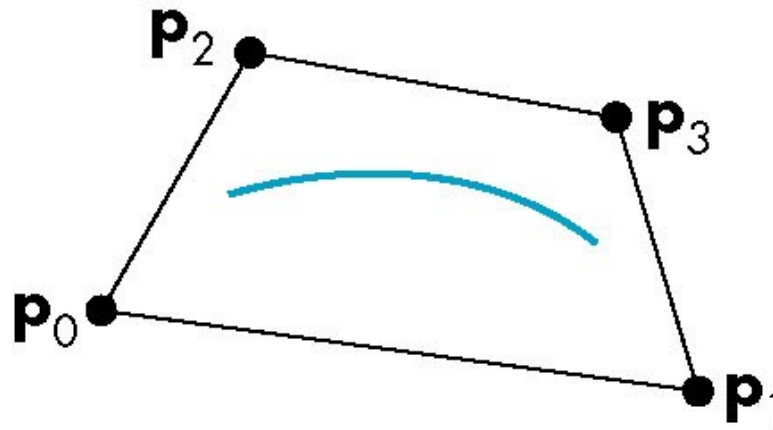
$$\mathbf{p}(u) = \mathbf{u}^T \mathbf{M}_S \mathbf{p} = \mathbf{b}(u)^T \mathbf{p}$$



# Convex Hull Property

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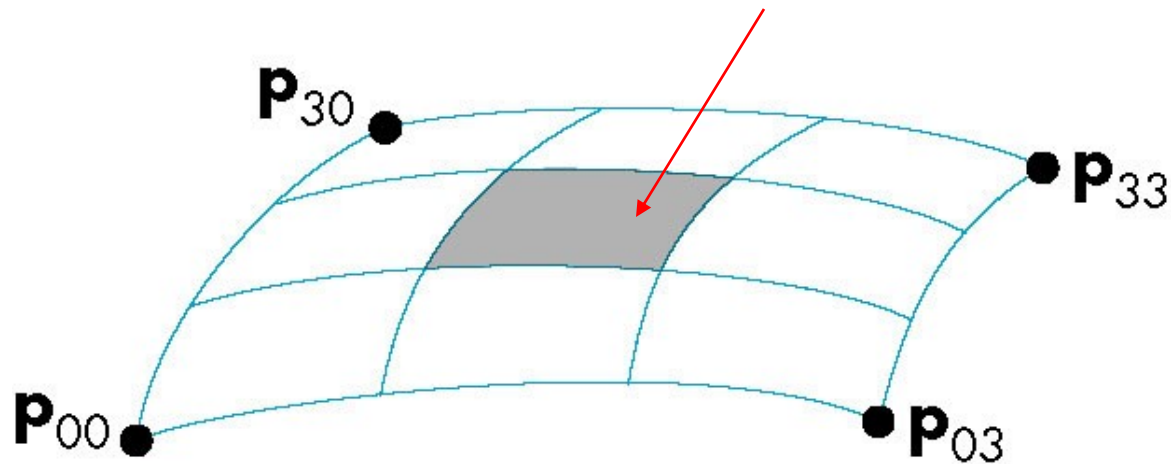
- For  $0 \leq u \leq 1$ , have  $0 \leq b_k(u) \leq 1$ ,  $\sum(b_k(u)) = 1$
- $p(u) = b_{i-2}(u)p_{i-2} + b_{i-1}(u)p_{i-1} + b_i(u)p_i + b_{i+1}(u)p_{i+1}$



# B-Spline Patches

$$p(u, v) = \sum_{i=0}^3 \sum_{j=0}^3 b_i(u) b_j(v) p_{ij} = \mathbf{u}^T \mathbf{M}_S \mathbf{P} \mathbf{M}_S^T \mathbf{v}$$

defined over only 1/9 of region



# Splines and Basis

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- If we examine the cubic B-spline from the perspective of each control (data) point, each interior point contributes (through the blending functions) to four segments
- We can rewrite  $p(u)$  in terms of the data points as

$$p(u) = \sum B_i(u) p_i$$

defining the basis functions  $\{B_i(u)\}$

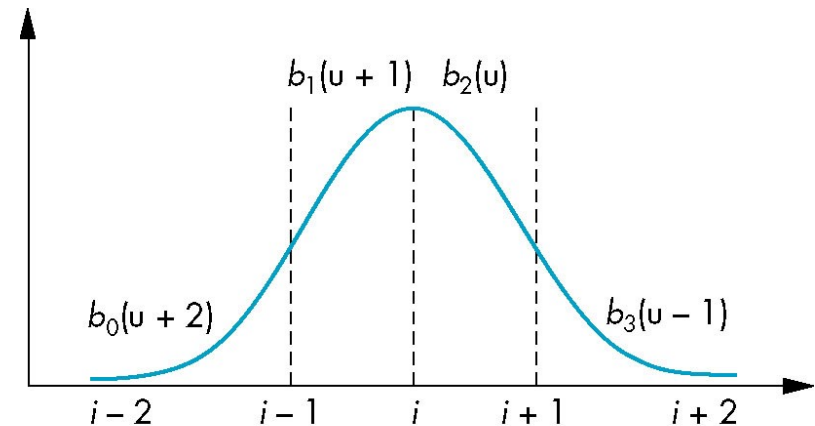
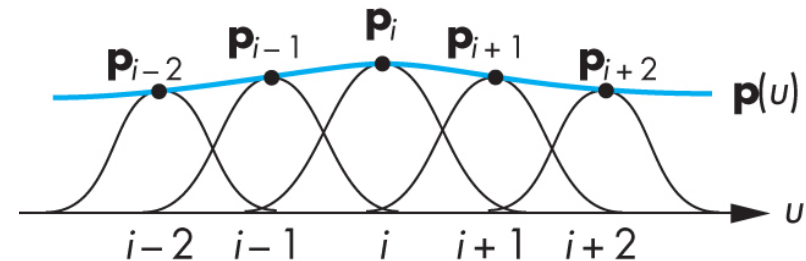




# Basis Functions

In terms of the blending polynomials,  
Total contribution  $B_i(u)p_i$  of  $p_i$  is given by

$$B_i(u) = \begin{cases} 0 & u < i-2 \\ b_0(u+2) & i-2 \leq u < i-1 \\ b_1(u+1) & i-1 \leq u < i \\ b_2(u) & i \leq u < i+1 \\ b_3(u-1) & i+1 \leq u < i+2 \\ 0 & u \geq i+2 \end{cases}$$



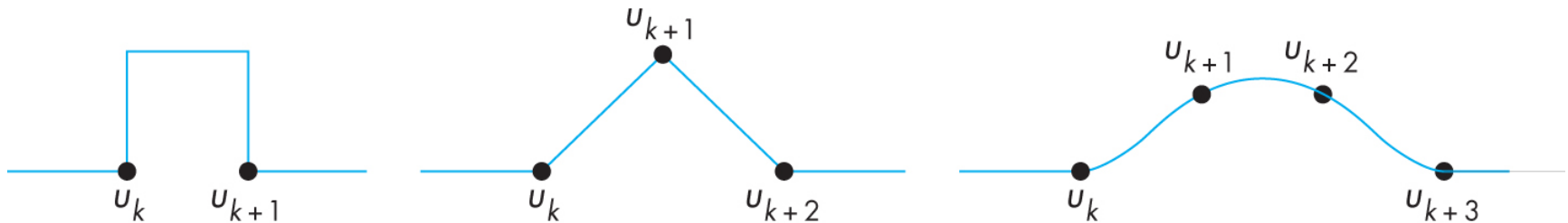
# Generalizing Splines

- Generalize from cubic to any degree
- Generalize to different basis function
  - Cox-deBoor recursion

$$p(u) = \sum_{i=0}^n B_{i,d}(u) P_i$$

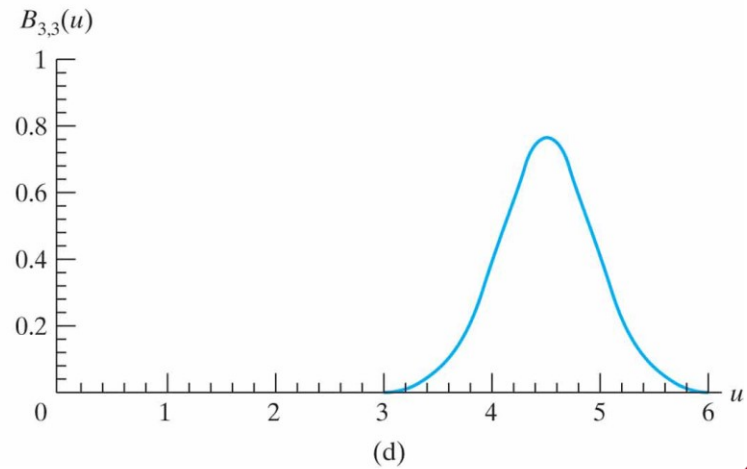
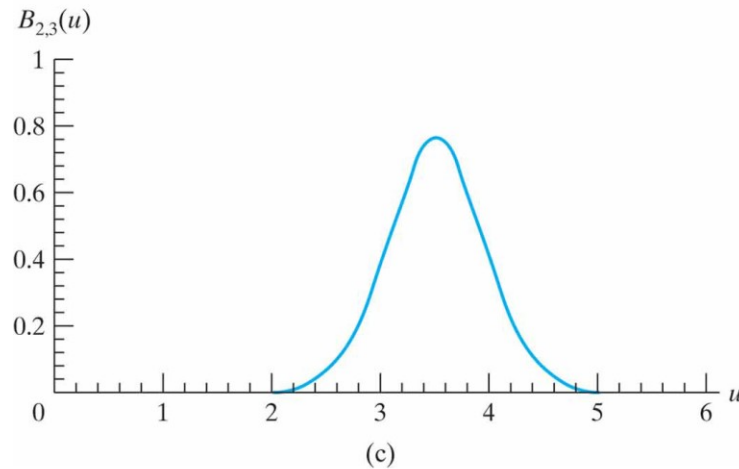
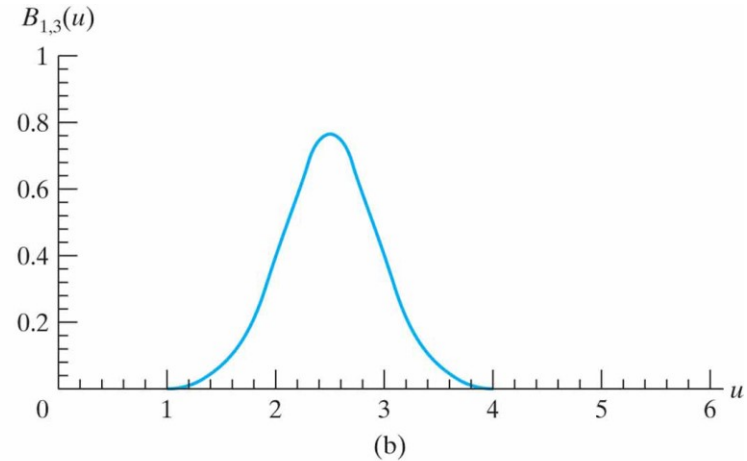
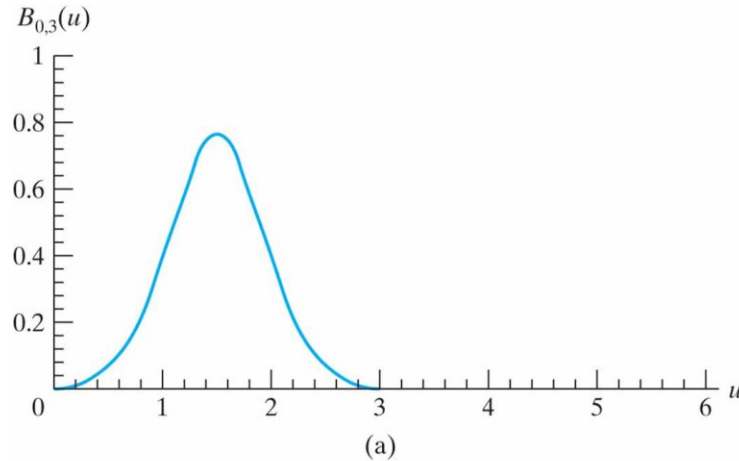
$$B_{k,0}(u) = \begin{cases} 1, & \text{if } u_k \leq u \leq u_{k+1} \\ 0, & \text{otherwise} \end{cases}$$

$$B_{k,d}(u) = \frac{u - u_k}{u_{k+d} - u_k} B_{k,d-1}(u) + \frac{u_{k+d+1} - u}{u_{k+d+1} - u_{k+1}} B_{k+1,d-1}(u)$$



# Quadratic B-spline

$d=2, n=4$



# Cubic B-Spline Summary

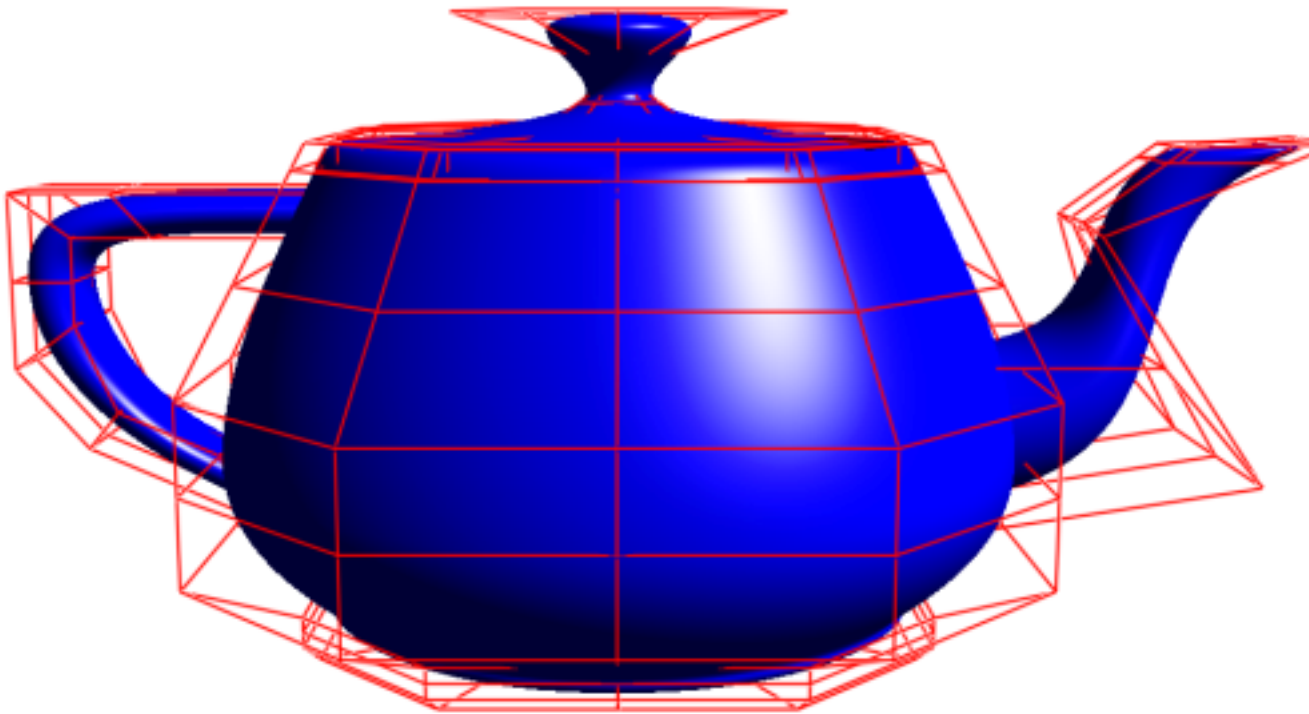
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- Expensive than Bezier to evaluate
- Smoother at joint point ( $C^2$ )
- Local control
  - Compact support defined by spline basis
- Easy to add points
  - Degree does not increase
- Convex hull property



# Questions?

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Bezier surface rendering of Utah teapot