Introduction to Computer Graphics

– Modeling (3) –

April 28, 2016

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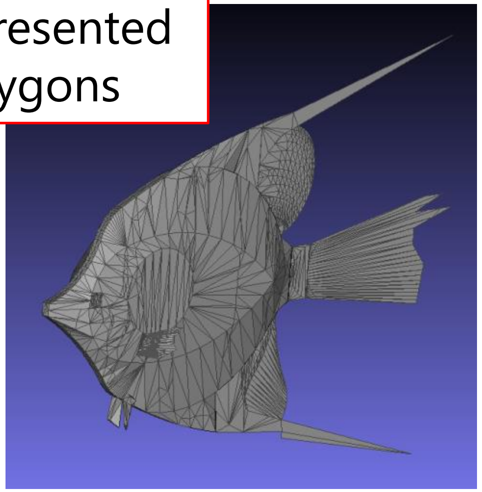
Solid modeling

Solid models

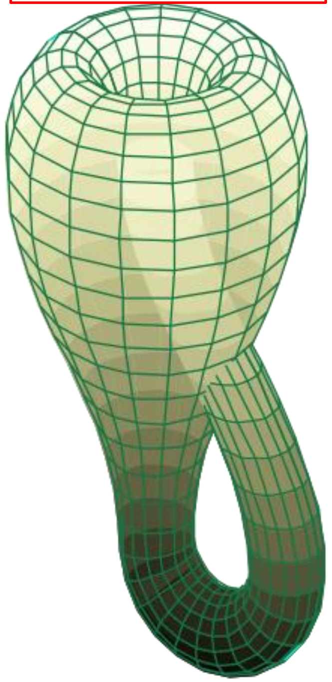
- Clear definition of “inside” & “outside” at any 3D point

Non-solid cases

Thin shapes represented by single polygons

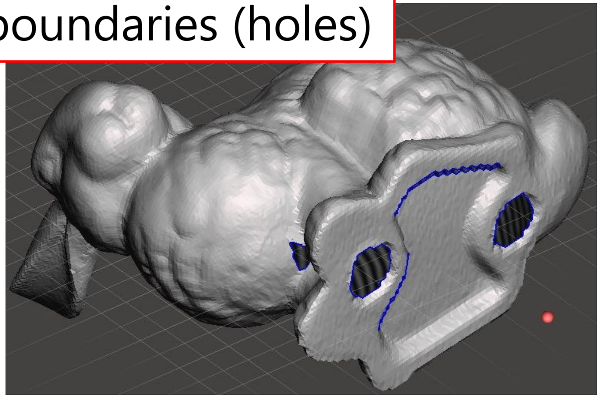


Unorientable

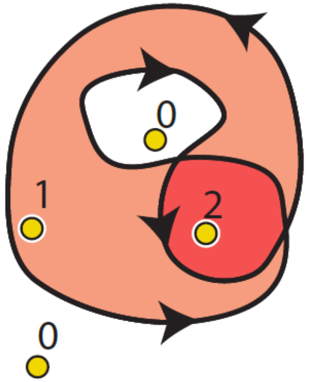


Klein bottle

Open boundaries (holes)

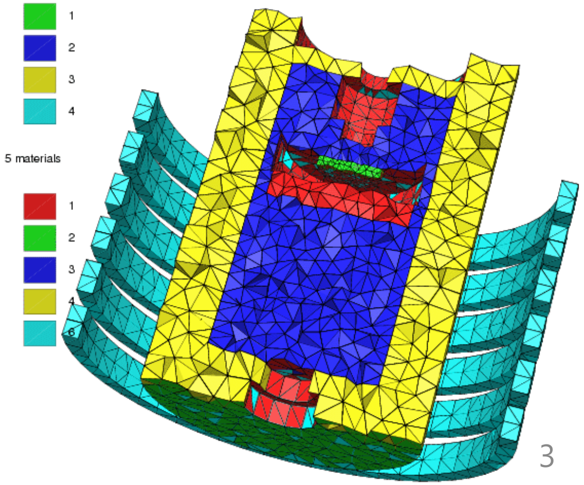


Self-intersections



- Main usage:

3D printing



Physics simulation

Predicate function of a solid model

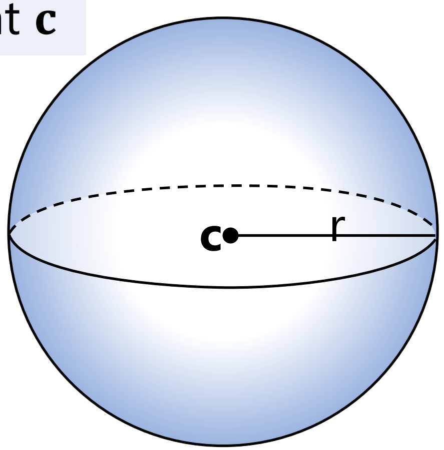
- Function that returns true/false if a 3D point $\mathbf{p} \in \mathbb{R}^3$ is inside/outside of the model $\quad f(\mathbf{p}): \mathbb{R}^3 \mapsto \{\, \text{true}, \text{false} \,\}$

- The whole interior of the model: $\{\, \mathbf{p} \mid f(\mathbf{p}) = \text{true} \,\} \subset \mathbb{R}^3$

- Examples:

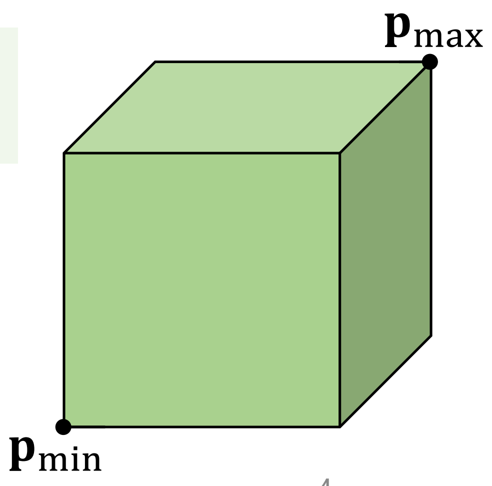
Sphere of radius r centered at $\mathbf{c}$

$$f(\mathbf{p}) \coloneqq \|\mathbf{p} - \mathbf{c}\| < r$$



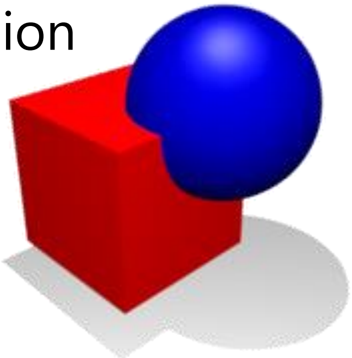
Box whose min & max corners are $(x_{\text{min}}, y_{\text{min}}, z_{\text{min}})$ & $(x_{\text{max}}, y_{\text{max}}, z_{\text{max}})$

$$\begin{aligned} f(x, y, z) \coloneqq\ & (x_{\text{min}} < x < x_{\text{max}}) \\ & \wedge (y_{\text{min}} < y < y_{\text{max}}) \\ & \wedge (z_{\text{min}} < z < z_{\text{max}}) \end{aligned}$$



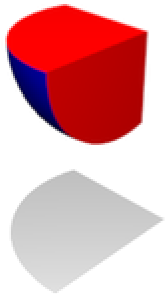
Constructive **S**olid **G**eometry (Boolean operations)

Union



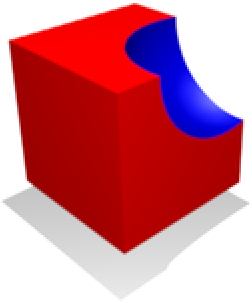
$$f_{A\cup B}(\mathbf{p}) \coloneqq f_A(\mathbf{p}) \vee f_B(\mathbf{p})$$

Intersection



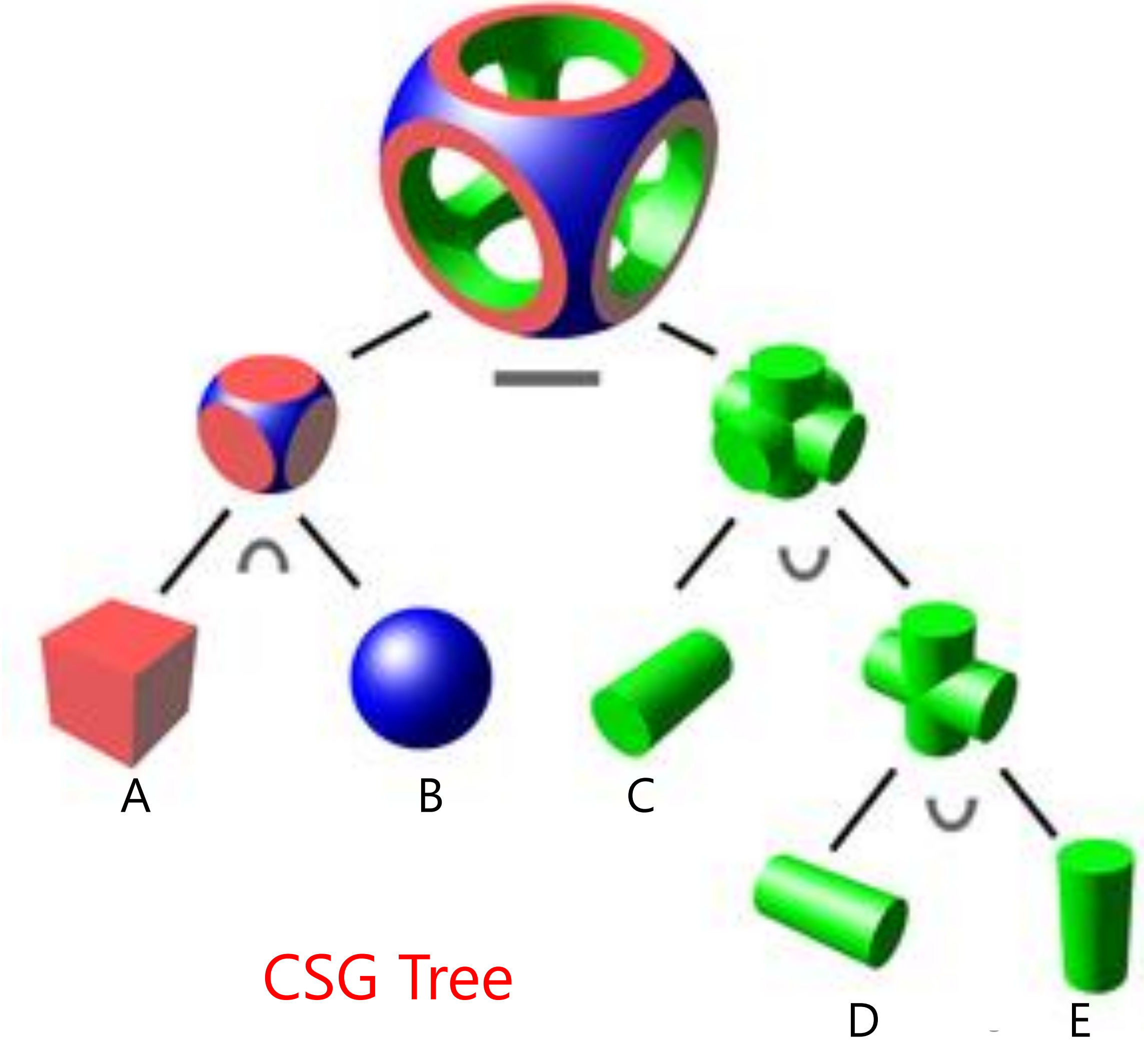
$$f_{A\cap B}(\mathbf{p}) \coloneqq f_A(\mathbf{p}) \wedge f_B(\mathbf{p})$$

Subtraction



$$f_{A\setminus B}(\mathbf{p}) \coloneqq f_A(\mathbf{p}) \wedge \neg f_B(\mathbf{p})$$

$(A \cap B) \setminus (C \cup (D \cup E))$



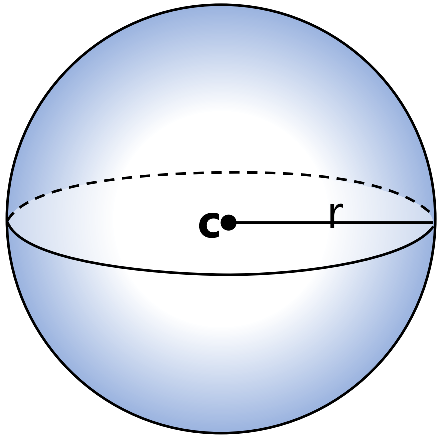
CSG Tree

Solid model represented by **S**inged **D**istance **F**ield

- Shortest distance from 3D point to model surface: $d(\mathbf{p}): \mathbb{R}^3 \mapsto \mathbb{R}$
  - Signed: positive/negative for outside/inside

Sphere of radius r centered at $\mathbf{c}$

$d(\mathbf{p}) \coloneqq \|\mathbf{p} - \mathbf{c}\| - r$



- Corresponding predicate: $f(\mathbf{p}) \coloneqq d(\mathbf{p}) < 0$

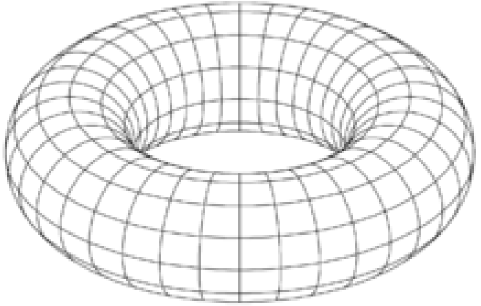
- Zero isosurface ➔ model surface: $\{\mathbf{p} \mid d(\mathbf{p}) = 0\} \subset \mathbb{R}^3$

- Aka. “implicit” or “volumetric” representation

- Gradient $\boldsymbol{\nabla} d(\mathbf{p})$ matches with normal direction

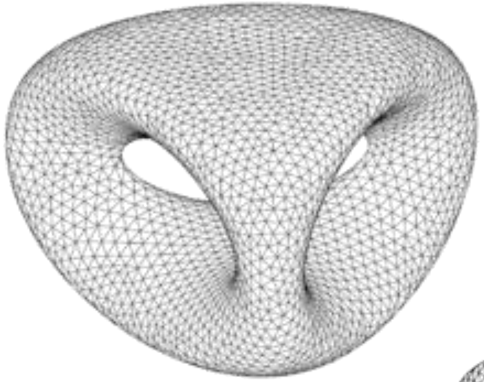
Examples of implicit functions

Not necessarily distance functions

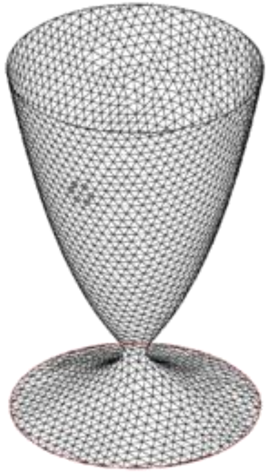


Torus with major & minor radii R & a

$$(x^2 + y^2 + z^2 + R^2 - a^2)^2 - 4R^2(x^2 + y^2) = 0$$



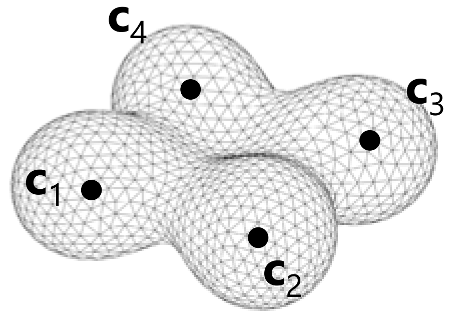
$$2y(y^2 - 3x^2)(1 - z^2) + (x^2 + y^2)^2 - (9z^2 - 1)(1 - z^2) = 0$$



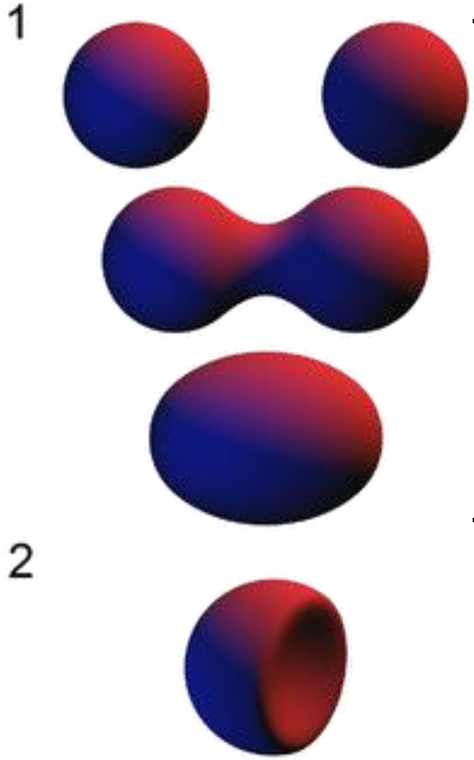
$$x^2 + y^2 - (\ln(z + 3.2))^2 - 0.02 = 0$$

Examples of implicit functions: Metaballs

$$d_i(\mathbf{p}) = \frac{q_i}{\|\mathbf{p} - \mathbf{c}_i\|} - r_i$$



$$d(\mathbf{p}) = d_1(\mathbf{p}) + d_2(\mathbf{p}) + d_3(\mathbf{p}) + d_4(\mathbf{p})$$



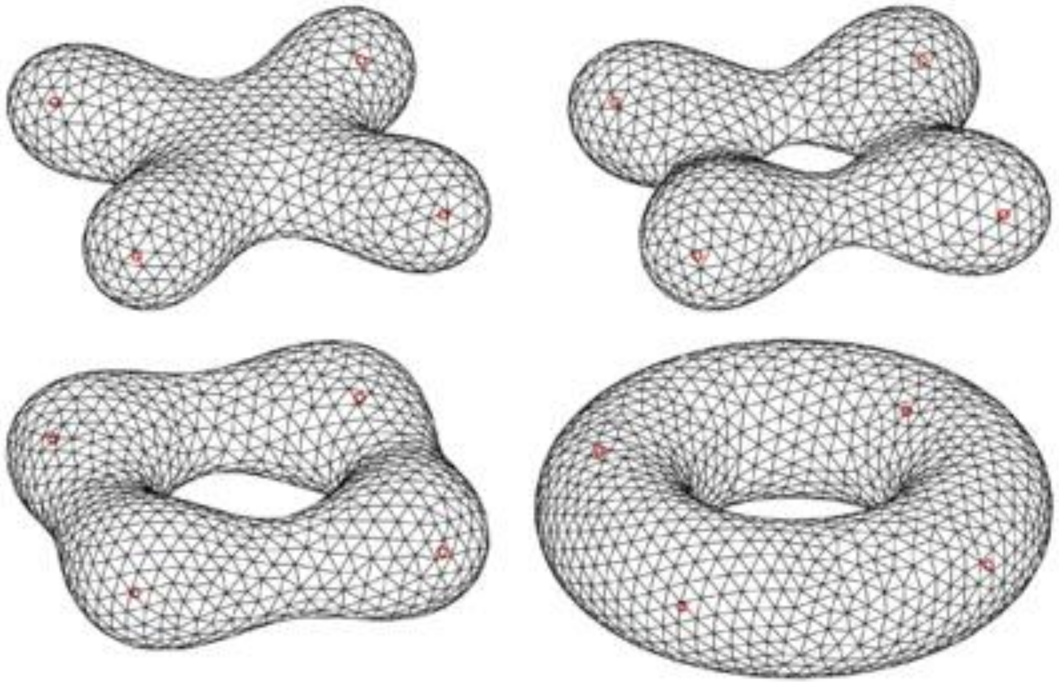
$$d(\mathbf{p}) = d_1(\mathbf{p}) + d_2(\mathbf{p})$$

$$d(\mathbf{p}) = d_1(\mathbf{p}) - d_2(\mathbf{p})$$

Morphing by interpolating implicit functions

$$d_1(\boldsymbol{p}) = 0$$

$$\frac{2}{3}d_1(\boldsymbol{p}) + \frac{1}{3}d_2(\boldsymbol{p}) = 0$$



$$\frac{1}{3}d_1(\boldsymbol{p}) + \frac{2}{3}d_2(\boldsymbol{p}) = 0$$

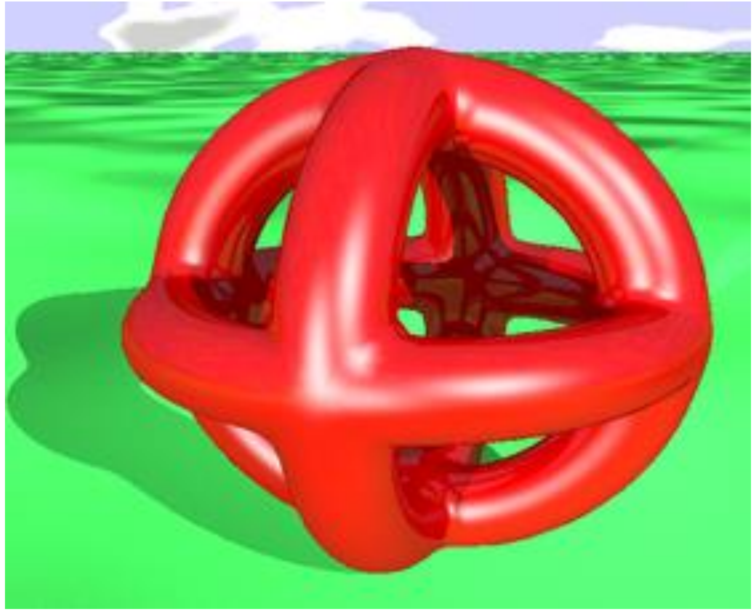
$$d_2(\boldsymbol{p}) = 0$$

Modeling by combining implicit functions

$$F_1 = (x^2 + y^2 + z^2 + R^2 - a^2)^2 - 4R^2(x^2 + y^2) = 0$$

$$F_2 = (x^2 + y^2 + z^2 + R^2 - a^2)^2 - 4R^2(x^2 + z^2) = 0$$

$$F_3 = (x^2 + y^2 + z^2 + R^2 - a^2)^2 - 4R^2(y^2 + z^2) = 0$$



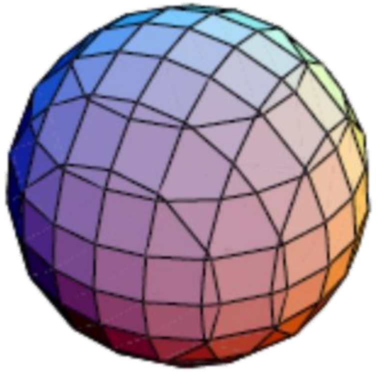
$$F(x, y, z) = F_1(x, y, z) \cdot F_2(x, y, z) \cdot F_3(x, y, z) - c = 0$$

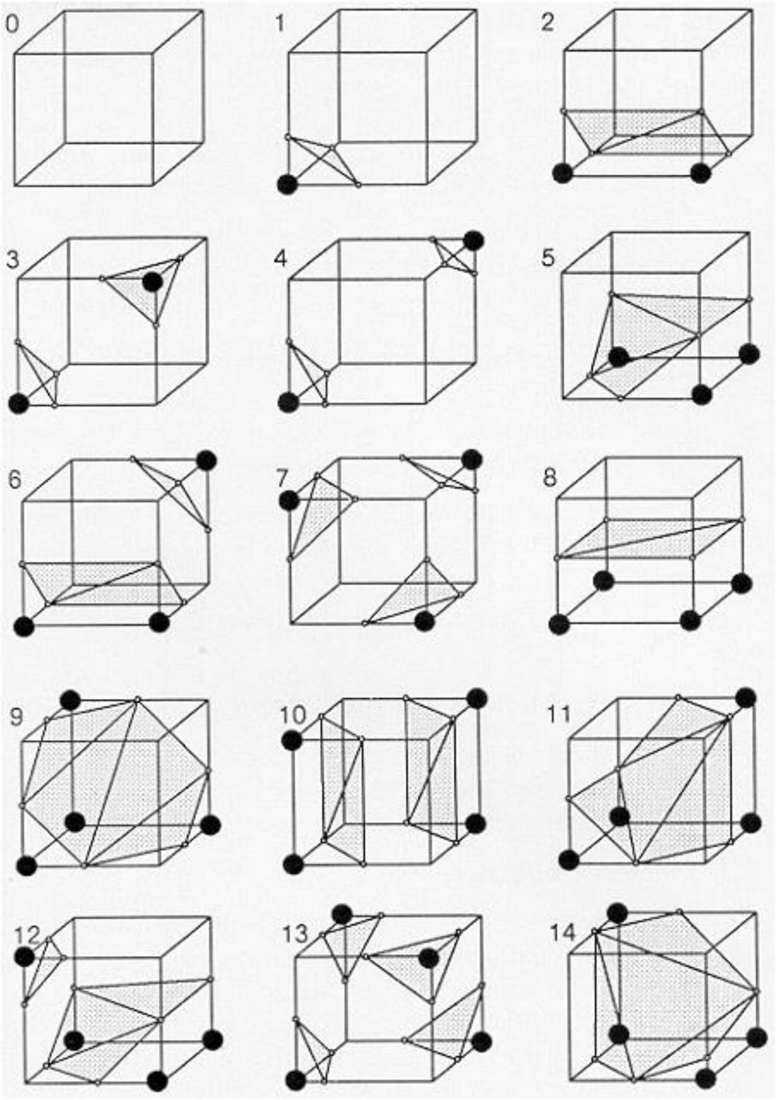
Visualizing implicit functions: Marching Cubes

- Extract isosurface as triangle mesh
- For every lattice cell:
  (1) Compute function values at 8 corners

  (2) Determine type of output triangles based on the sign pattern
    - Classified into 15 using symmetry

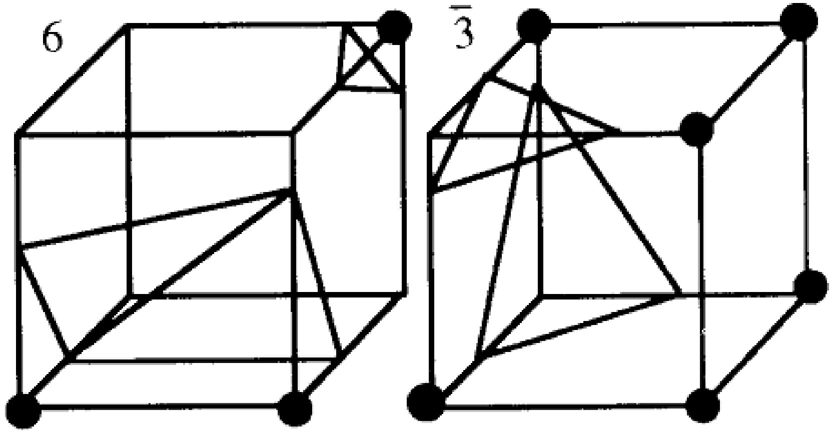
  (3) Determine vertex positions by linearly interpolating function values
- Once with patent issue☹, now expired☺



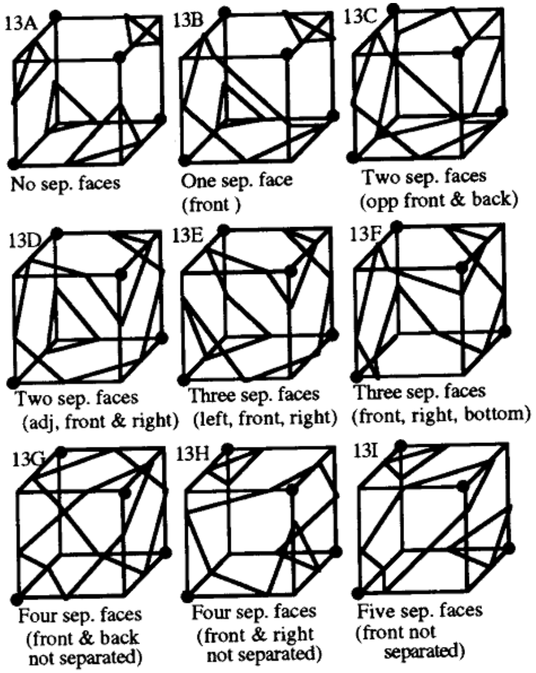


Marching Cubes: A High Resolution 3D Surface Construction Algorithm [Lorensen SIGGRAPH87]

Ambiguity in Marching Cubes



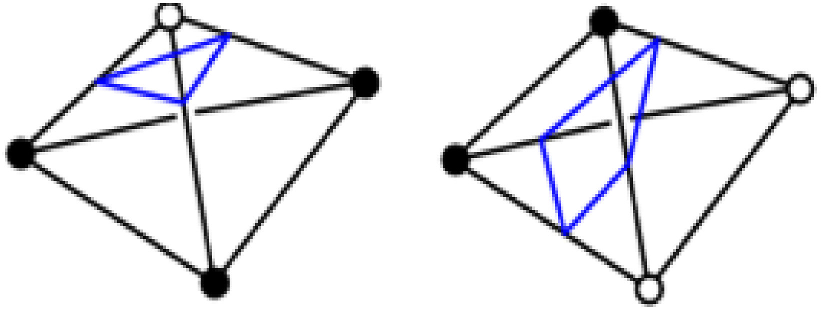
Discontinuous faces across neighboring cells



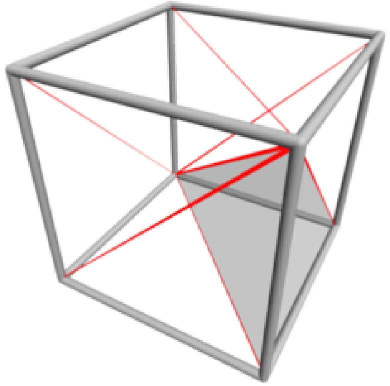
New rules to resolve ambiguity

The asymptotic decider: resolving the ambiguity in marching cubes [Nielson VIS91]

Marching Tetrahedra

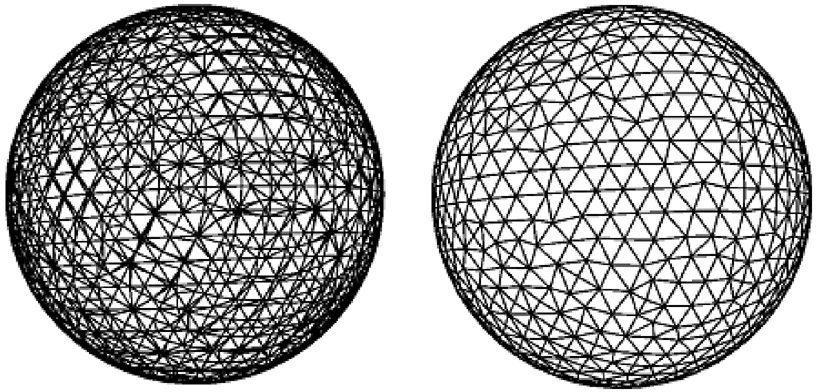


- Use tetrahedra instead of cubes
  - Fewer patterns, no ambiguity
    ➔ Simpler implementation



- A cube split into 6 tetrahedra
  - (Make sure consistent splitting across neighboring cubes)

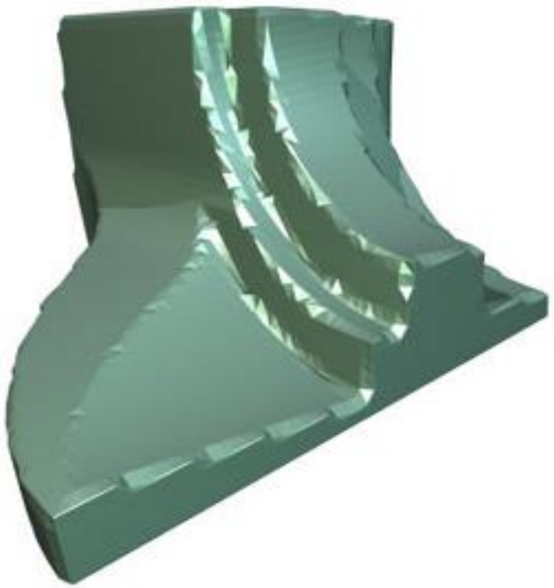
- Some techniques to improve mesh quality



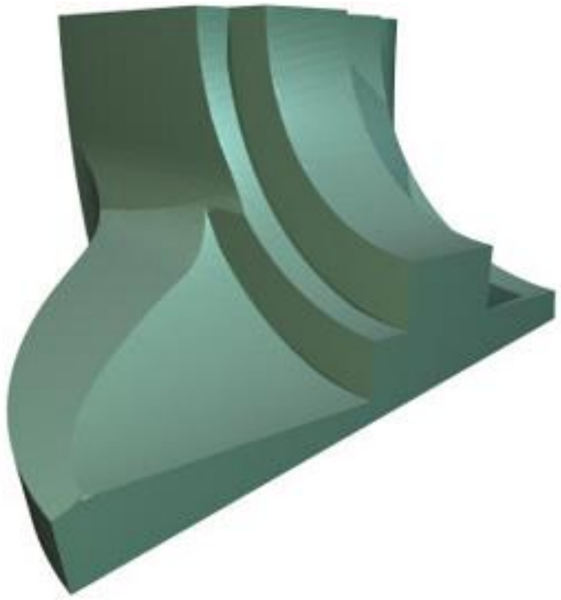
http://paulbourke.net/geometry/polygonise/
Regularised marching tetrahedra: improved iso-surface extraction [Treece C&G99]

Isosurface extraction preserving sharp edges

Grid size: 65×65×65

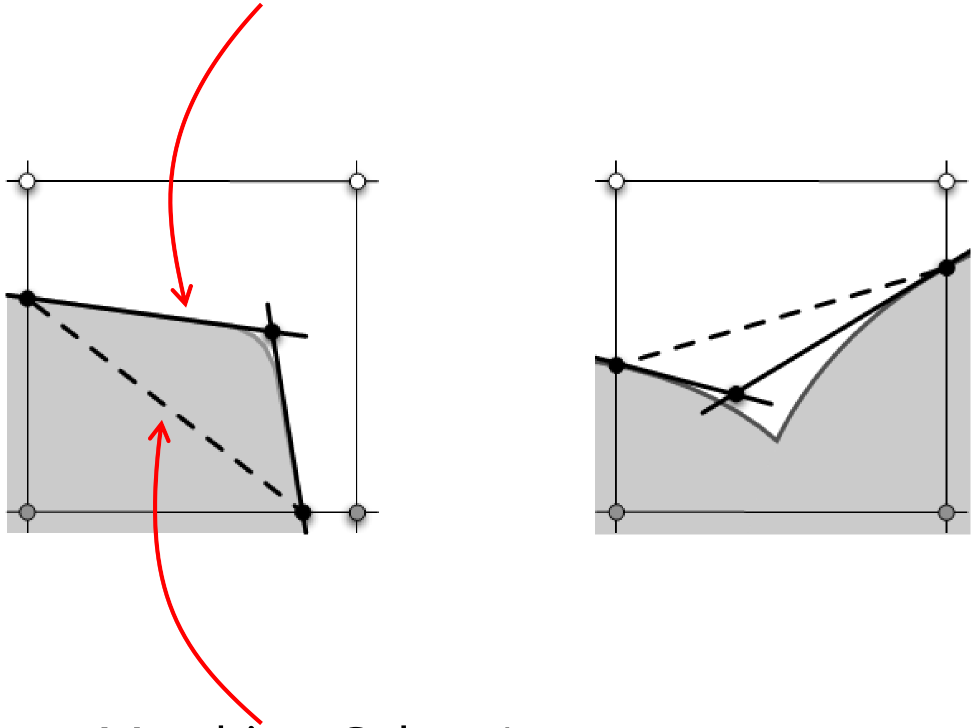


Marching Cubes



Improved version

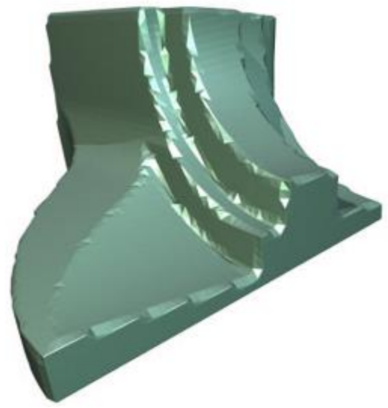
Improved version (uses function *gradient* as well)



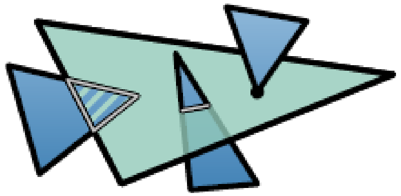
Marching Cubes (only uses function values)

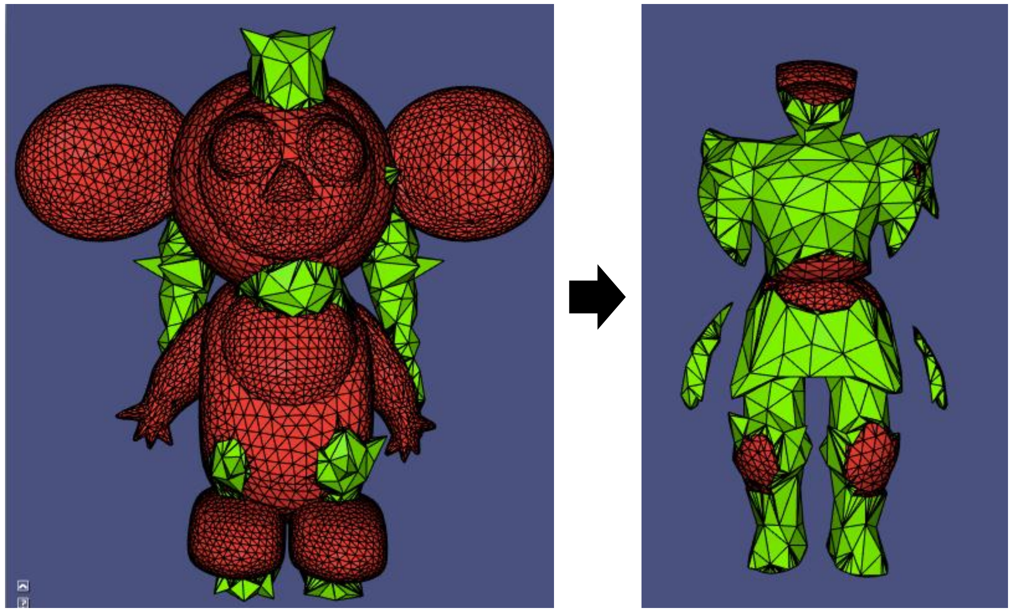
Feature Sensitive Surface Extraction from Volume Data [Kobbelt SIGGRAPH01]
Dual Contouring of Hermite Data [Ju SIGGRAPH02]
http://www.graphics.rwth-aachen.de/IsoEx/

CSG with surface representation only



- Volumetric representation (=isosurface extraction using MC)
  ➔ Approximation accuracy depends on grid resolution ☹
- CSG with surface representation only
  ➔ Exactly keep original mesh geometry ☺
- Difficult to implement robust & efficient ☹
  - Floating point error
  - Exactly coplanar faces



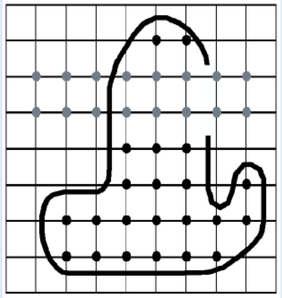


- Notable advances in recent years

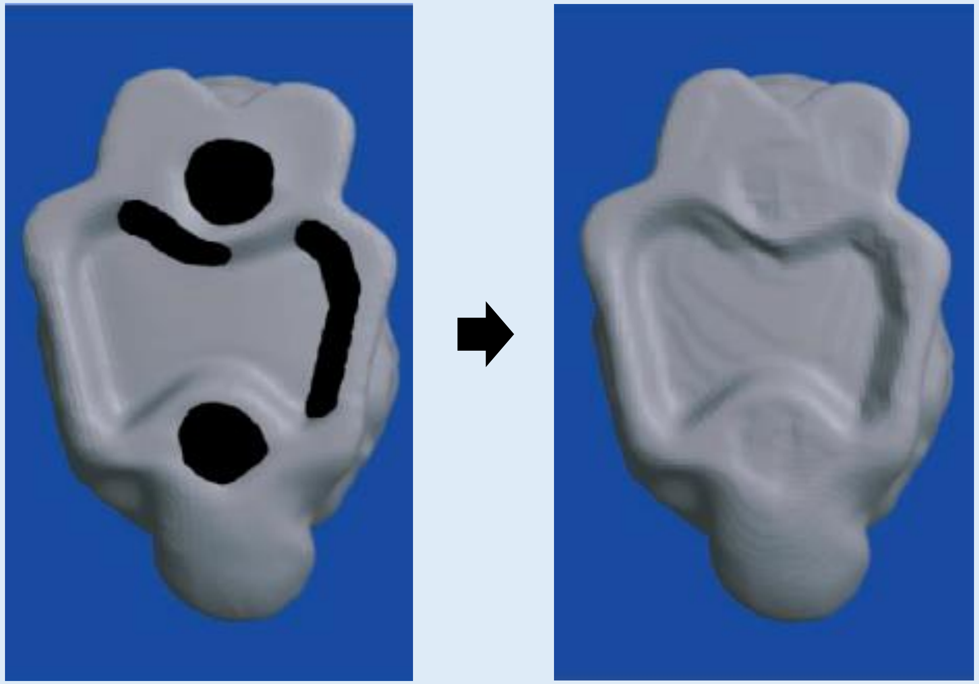
Fast, exact, linear booleans [Bernstein SGP09]
Exact and Robust (Self-)Intersections for Polygonal Meshes [Campen EG10]
Mesh Arrangements for Solid Geometry [Zhou SIGGRAPH16]
https://libigl.github.io/libigl/tutorial/tutorial.html#booleanoperationsonmeshes

Mesh repair

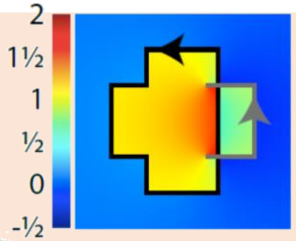
Volumetric representation



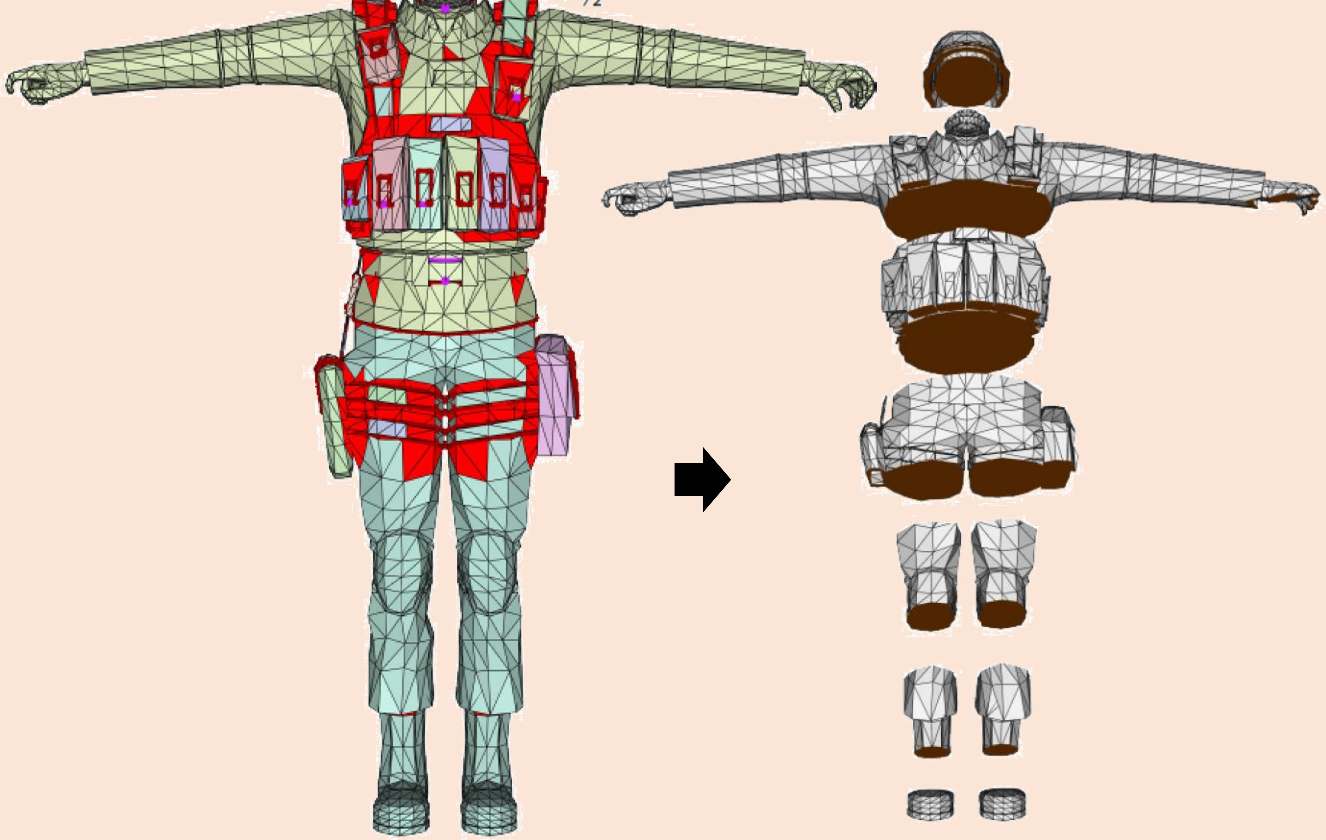
Decide inside/outside by shooting rays from outside



Surface representation



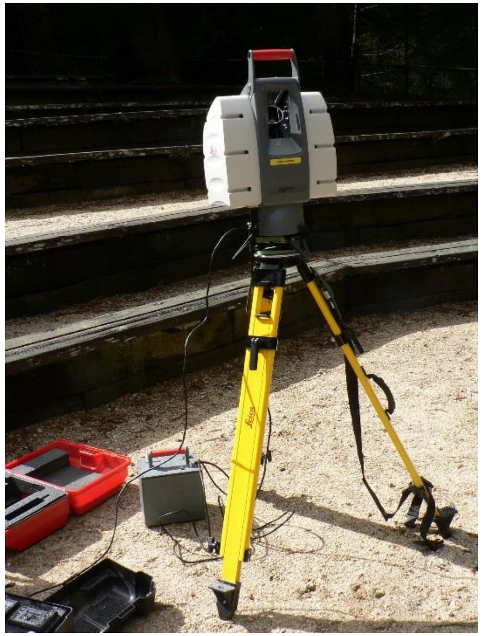
Decide inside/outside based on generalized winding number



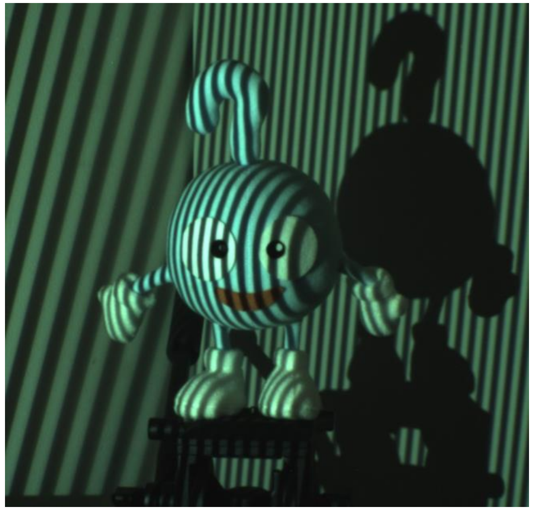
Simplification and Repair of Polygonal Models Using Volumetric Techniques [Nooruddin TVCG03]
Robust Inside-Outside Segmentation using Generalized Winding Numbers [Jacobson SIGGRAPH13]

Surface reconstruction from point cloud

Measuring 3D shapes

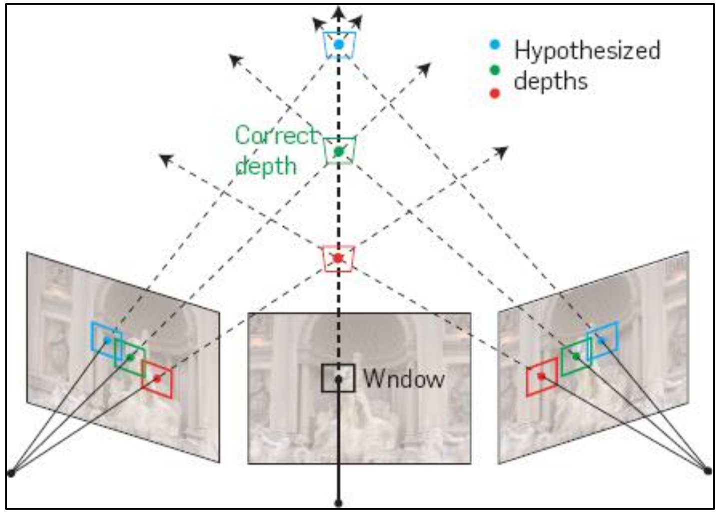


Range Scanner (LIDAR)



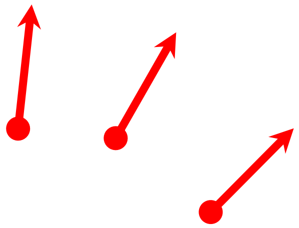
Structured Light

Depth Camera



Multi-View Stereo

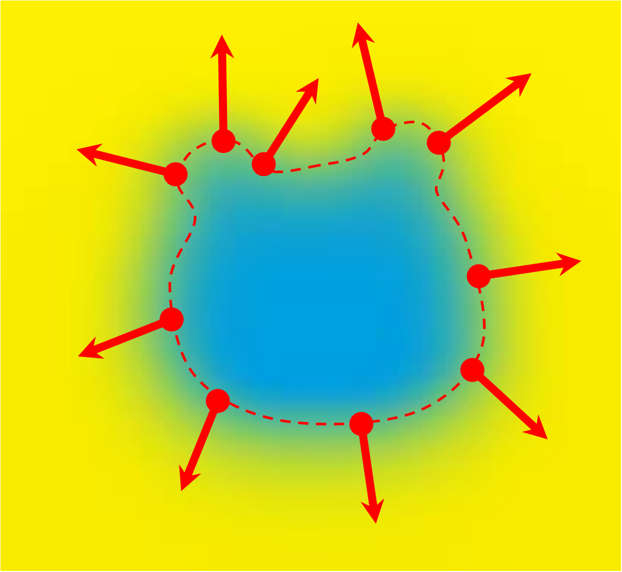
- Obtained data: point cloud
  - 3D coordinate
  - Normal (surface orientation)
    - Not always available
  - Sometimes noise-laden



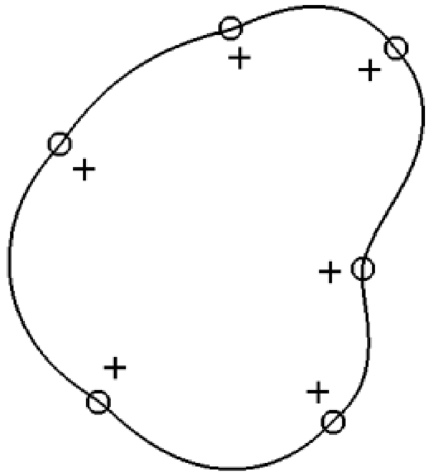
Surface reconstruction from point cloud

- Input: N points
  - Coordinate $\mathbf{x}_i = (x_i, y_i, z_i)$ & normal $\mathbf{n}_i = \left(n_i^{\mathrm{x}}, n_i^{\mathrm{y}}, n_i^{\mathrm{z}}\right)$, $i \in \{1, \dots, N\}$
- Output: function $f(\mathbf{x})$ satisfying value & gradient constraints
  - $f(\mathbf{x}_i) = f_i$
  - $\nabla f(\mathbf{x}_i) = \mathbf{n}_i$
  - Zero isosurface $f(\mathbf{x}) = 0$ ➔ output surface
- "Scattered Data Interpolation"
  - **M**oving **L**east **S**quares
  - **R**adial **B**asis **F**unction

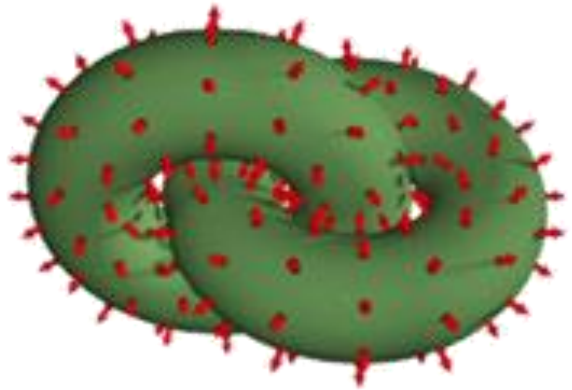
Important to other fields (e.g. Machine Learning) as well



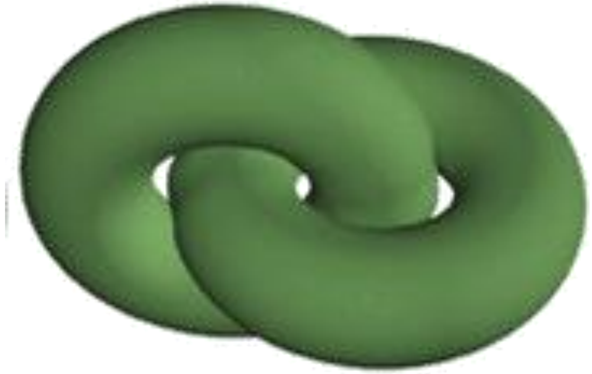
Two ways for controlling gradients



- Additional value constraints at offset locations
  - Simple
- Directly include gradient constraint in the mathematical formulation (Hermite interpolation)
  - High-quality



Value+gradient constraints



Hermite interpolation

Simple offsetting

Modelling with implicit surfaces that interpolate [Turk TOG02]
Hermite Radial Basis Functions Implicits [Macedo CGF10]

Interpolation using **M**oving **L**east **S**quares

Starting point: Least **SQ**uares

- For now, assume the function as linear: $f(\mathbf{x}) = ax + by + cz + d$
  - Unknowns: a, b, c, d

$\mathbf{x} := (x, y, z)$

- Value constraints at data points

$$
\begin{aligned}
f(\mathbf{x}_1) &= ax_1 + by_1 + cz_1 + d = f_1 \\
f(\mathbf{x}_2) &= ax_2 + by_2 + cz_2 + d = f_2 \\
&\vdots \\
f(\mathbf{x}_N) &= ax_N + by_N + cz_N + d = f_N
\end{aligned}
$$

$$
\underbrace{\begin{bmatrix} x_1 & y_1 & z_1 & 1 \\ x_2 & y_2 & z_2 & 1 \\ & \vdots & & \\ x_N & y_N & z_N & 1 \end{bmatrix}}_{A}
\underbrace{\begin{bmatrix} a \\ b \\ c \\ d \end{bmatrix}}_{\mathbf{c}}
=
\underbrace{\begin{bmatrix} f_1 \\ f_2 \\ \vdots \\ f_N \end{bmatrix}}_{\mathbf{f}}
$$

- (Forget about gradient constraints for now)

Overconstrained System

- #unknowns < #constraints (i.e. taller matrix)
  ➔ cannot exactly satisfy all the constraints

"normal equation"

$$A\,\mathbf{c} = \mathbf{f} \quad \Rightarrow \quad A^{\top} A\,\mathbf{c} = A^{\top}\mathbf{f}$$

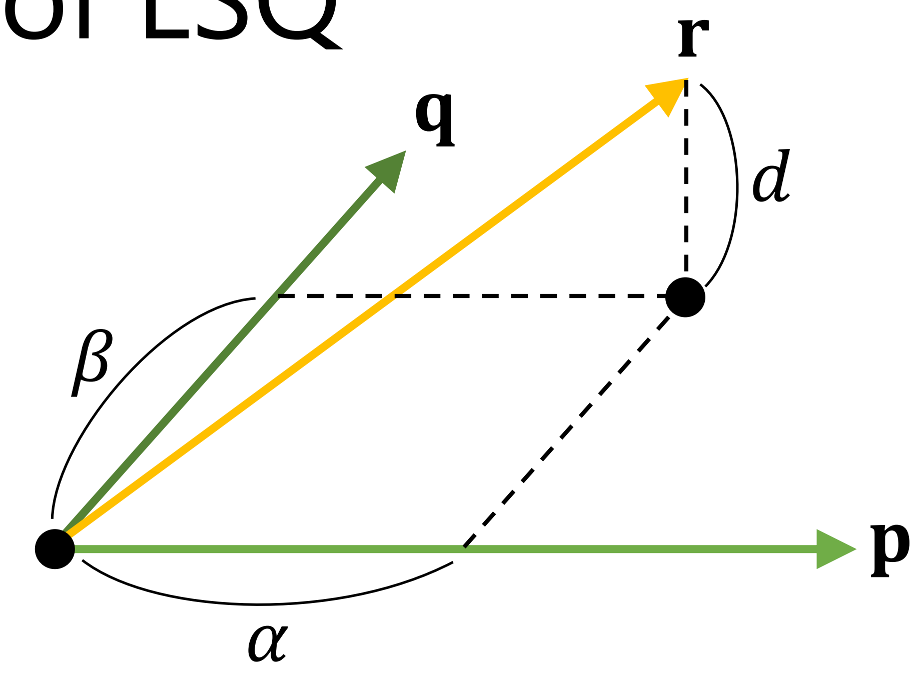
- Minimizing fitting error

$$\|A\,\mathbf{c} - \mathbf{f}\|^2 = \sum_{i=1}^{N} \|f(\mathbf{x}_i) - f_i\|^2$$

$$\mathbf{c} = (A^{\top}A)^{-1} A^{\top}\mathbf{f}$$

Geometric interpretation of LSQ

$$\begin{bmatrix} p_{\mathrm{x}} & q_{\mathrm{x}} \\ p_{\mathrm{y}} & q_{\mathrm{y}} \\ p_{\mathrm{z}} & q_{\mathrm{z}} \end{bmatrix} \begin{bmatrix} \alpha \\ \beta \end{bmatrix} = \begin{bmatrix} r_{\mathrm{x}} \\ r_{\mathrm{y}} \\ r_{\mathrm{z}} \end{bmatrix}$$



- Project $\mathbf{r}$ onto a plane spanned by $\mathbf{p}$ & $\mathbf{q}$
  - Fitting error = projection distance

$$d^2 = \|\alpha\mathbf{p} + \beta\mathbf{q} - \mathbf{r}\|^2$$

Weighted **L**east **S**quares

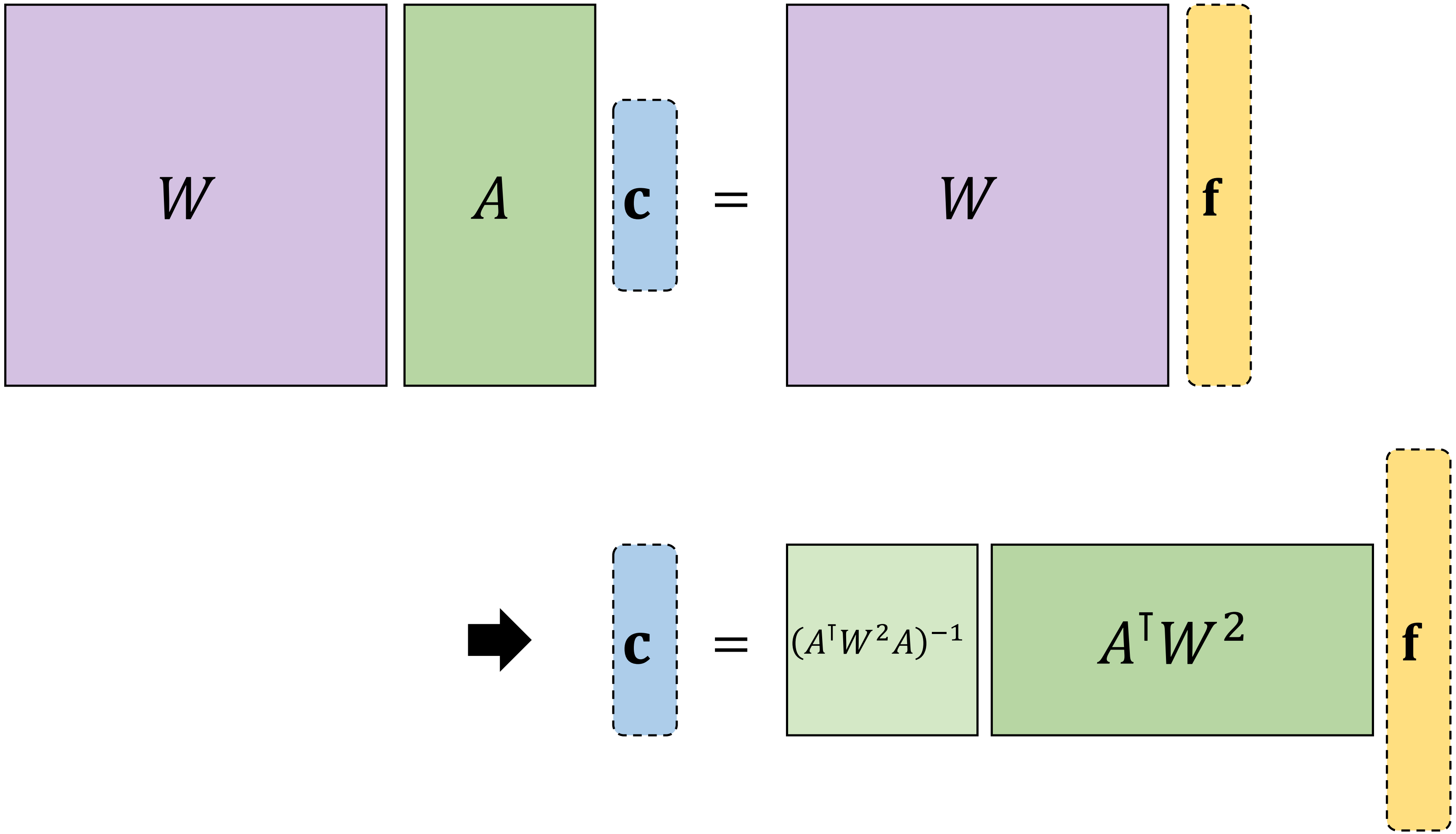
- Each data point is weighted by w_i
  - Importance, confidence, …

- Minimize the following fitting error:

$$\sum_{i=1}^{N} \|w_i(f(\mathbf{x}_i) - f_i)\|^2$$

$$\underbrace{\begin{bmatrix} w_1 & & & \\ & w_2 & & \\ & & \ddots & \\ & & & w_N \end{bmatrix}}_{W} \underbrace{\begin{bmatrix} x_1 & y_1 & z_1 & 1 \\ x_2 & y_2 & z_2 & 1 \\ & \vdots & & \\ x_N & y_N & z_N & 1 \end{bmatrix}}_{A} \underbrace{\begin{bmatrix} a \\ b \\ c \\ d \end{bmatrix}}_{\mathbf{c}} = \underbrace{\begin{bmatrix} w_1 & & & \\ & w_2 & & \\ & & \ddots & \\ & & & w_N \end{bmatrix}}_{W} \underbrace{\begin{bmatrix} f_1 \\ f_2 \\ \vdots \\ f_N \end{bmatrix}}_{\mathbf{f}}$$

Weighted Least Squares



Moving **L**east **S**quares

- Weight w_i is a function of evaluation point $\mathbf{x}$:

$$w_i(\mathbf{x}) = w(\|\mathbf{x} - \mathbf{x}_i\|)$$

- Popular choices for the function (kernel):
  - $w(r) = e^{-r^2/\sigma^2}$
  - $w(r) = \frac{1}{r^2+\epsilon^2}$

Larger the weight as $\mathbf{x}$ is closer to $\mathbf{x}_i$

- Weighting matrix W is a function of $\mathbf{x}$

  ➔ Coeffs a, b, c, d are functions of $\mathbf{x}$

$$f(\mathbf{x}) = [\,x \;\; y \;\; z \;\; 1\,] \begin{bmatrix} a(\mathbf{x}) \\ b(\mathbf{x}) \\ c(\mathbf{x}) \\ d(\mathbf{x}) \end{bmatrix}$$

$$f(\mathbf{x}) = [\,x \;\; y \;\; z \;\; 1\,] \, (A^\top W(\mathbf{x})^2 A)^{-1} \; A^\top W(\mathbf{x})^2 \; \mathbf{f}$$

Introducing gradient (normal) constraints

- Consider linear function represented by each data point:

$$g_i(\mathbf{x}) = f_i + (\mathbf{x} - \mathbf{x}_i)^\top \mathbf{n}_i$$

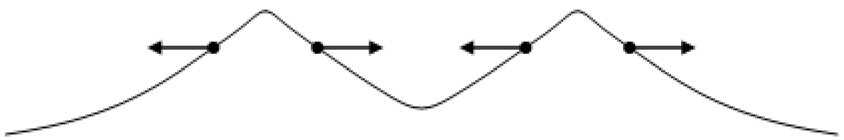
- Minimize fitting error to each g_i evaluated at $\mathbf{x}$:

$$\sum_{i=1}^{N} \left\| w_i(\mathbf{x}) \big(f(\mathbf{x}) - g_i(\mathbf{x}) \big) \right\|^2$$

$$\begin{bmatrix} w_1(\mathbf{x}) & & & \\ & w_2(\mathbf{x}) & & \\ & & \ddots & \\ & & & w_N(\mathbf{x}) \end{bmatrix} \begin{bmatrix} x & y & z & 1 \\ x & y & z & 1 \\ & \vdots & & \\ x & y & z & 1 \end{bmatrix} \begin{bmatrix} a \\ b \\ c \\ d \end{bmatrix} = \begin{bmatrix} w_1(\mathbf{x}) & & & \\ & w_2(\mathbf{x}) & & \\ & & \ddots & \\ & & & w_N(\mathbf{x}) \end{bmatrix} \begin{bmatrix} g_1(\mathbf{x}) \\ g_2(\mathbf{x}) \\ \vdots \\ g_N(\mathbf{x}) \end{bmatrix}$$

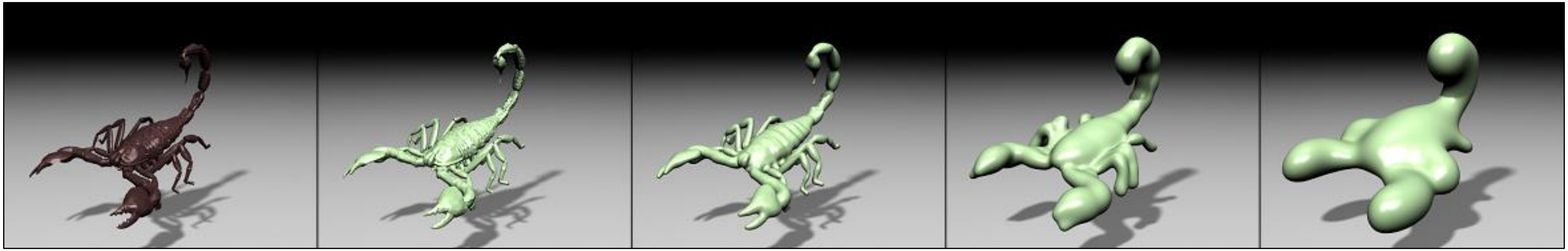
Interpolating and Approximating Implicit Surfaces from Polygon Soup [Shen SIGGRAPH04]

Introducing gradient (normal) constraints



Normal constraints

Simple offsetting



Input : Polygon Soup Interpolation Approximation 1 Approximation 2 Approximation 3

Interpolating and Approximating Implicit Surfaces from Polygon Soup [Shen SIGGRAPH04]

Interpolation using **R**adial **B**asis **F**unctions

Basic idea

- Define $f(\mathbf{x})$ as weighted sum of basis functions $\phi(\mathbf{x})$:

$$f(\mathbf{x}) = \sum_{i=1}^{N} w_i \phi(\mathbf{x} - \mathbf{x}_i)$$

Basis function translated to each data point $\mathbf{x}_i$

- Radial Basis Function $\phi(\mathbf{x})$: only depends on the length of $\mathbf{x}$
  - $\phi(\mathbf{x}) = e^{-\|\mathbf{x}\|^2/\sigma^2}$ (Gaussian)
  - $\phi(\mathbf{x}) = \frac{1}{\sqrt{\|\mathbf{x}\|^2 + c^2}}$ (Inverse Multiquadric)

- Determine weights w_i from constraints at data points $f(\mathbf{x}_i) = f_i$

Basic idea

Notation: $\phi_{i,j} = \phi(\mathbf{x}_i - \mathbf{x}_j)$

$$f(\mathbf{x}_1) = w_1\phi_{1,1} + w_2\phi_{1,2} + \cdots + w_N\phi_{1,N} = f_1$$

$$f(\mathbf{x}_2) = w_1\phi_{2,1} + w_2\phi_{2,2} + \cdots + w_N\phi_{2,N} = f_2$$

$$\vdots$$

$$f(\mathbf{x}_N) = w_1\phi_{N,1} + w_2\phi_{N,2} + \cdots + w_N\phi_{N,N} = f_N$$

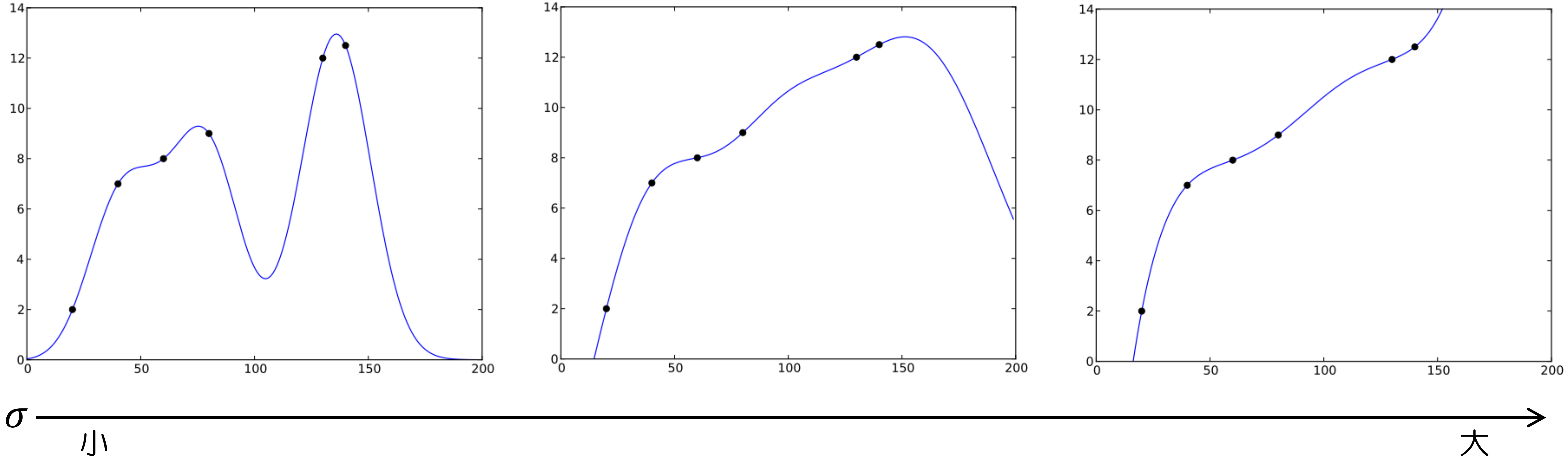
$$\underbrace{\begin{bmatrix} \phi_{1,1} & \phi_{1,2} & & \phi_{1,N} \\ \phi_{2,1} & \phi_{2,2} & & \phi_{2,N} \\ & & \ddots & \\ \phi_{N,1} & \phi_{N,2} & & \phi_{N,N} \end{bmatrix}}_{\Phi} \underbrace{\begin{bmatrix} w_1 \\ w_2 \\ \vdots \\ w_N \end{bmatrix}}_{\mathbf{w}} = \underbrace{\begin{bmatrix} f_1 \\ f_2 \\ \vdots \\ f_N \end{bmatrix}}_{\mathbf{f}}$$

Solve this!

When using Gaussian RBF

$$\phi(\mathbf{x}) = e^{-\|\mathbf{x}\|^2/\sigma^2}$$

- Results highly dependent on the choice of parameter σ ☹



- How to obtain the as-smooth-as-possible result?

Measuring function’s “bend”: Thin-Plate Energy

- 2nd derivative (=curvature) magnitude integrated over the whole domain

$$E_2[f] = \int_{\mathbf{x}\in\mathbb{R}^d} \|\Delta f(\mathbf{x})\|^2 d\mathbf{x}$$

  - 1D case:

$$E_2[f] = \int_{x\in\mathbb{R}} f''(x)^2 dx$$

  - 2D case:

$$E_2[f] = \int_{\mathbf{x}\in\mathbb{R}^2} \left(f_{\mathrm{xx}}(\mathbf{x})^2 + 2f_{\mathrm{xy}}(\mathbf{x})^2 + f_{\mathrm{yy}}(\mathbf{x})^2\right) d\mathbf{x}$$

  - 3D case:

$$E_2[f] = \int_{\mathbf{x}\in\mathbb{R}^3} \left(f_{\mathrm{xx}}(\mathbf{x})^2 + f_{\mathrm{yy}}(\mathbf{x})^2 + f_{\mathrm{zz}}(\mathbf{x})^2 + 2f_{\mathrm{xy}}(\mathbf{x})^2 + 2f_{\mathrm{yz}}(\mathbf{x})^2 + 2f_{\mathrm{zx}}(\mathbf{x})^2\right) d\mathbf{x}$$

Known theory in the math literature

- Of all functions satisfying $\{ f(\mathbf{x}_i) = f_i \}$, the minimizer of E_2 is represented as RBFs with the following basis:
  - 1D case: $\phi(x) = |x|^3$
  - 2D case: $\phi(\mathbf{x}) = \|\mathbf{x}\|^2 \log \|\mathbf{x}\|$
  - 3D case: $\phi(\mathbf{x}) = \|\mathbf{x}\|$
- FYI
  - Finite Element Method: Find f minimizing E_2 discretized over mesh
  - RBF: Find f minimizing E_2 analytically

Additional linear term

- $E_2[f]$ is defined using 2nd derivative
  ➔ Any additional linear term $p(\mathbf{x}) = ax + by + cz + d$ has no effect:

$$E_2[f + p] = E_2[f]$$

- Make f unique by regarding linear term as additional unknowns:

$$f(\mathbf{x}) = \sum_{i=1}^{N} w_i \, \phi(\mathbf{x} - \mathbf{x}_i) + ax + by + cz + d$$

With linear term

$$f(\mathbf{x}_1) = w_1\phi_{1,1} + w_2\phi_{1,2} + \cdots + w_N\phi_{1,N} + ax_1 + by_1 + cz_1 + d = f_1$$

$$f(\mathbf{x}_2) = w_1\phi_{2,1} + w_2\phi_{2,2} + \cdots + w_N\phi_{2,N} + ax_2 + by_2 + cz_2 + d = f_2$$

$$\vdots$$

$$f(\mathbf{x}_N) = w_1\phi_{N,1} + w_2\phi_{N,2} + \cdots + w_N\phi_{N,N} + ax_N + by_N + cz_N + d = f_N$$

$$\left[\begin{array}{cccc|cccc} \phi_{1,1} & \phi_{1,2} & & \phi_{1,N} & x_1 & y_1 & z_1 & 1 \\ \phi_{2,1} & \phi_{2,2} & & \phi_{2,N} & x_2 & y_2 & z_2 & 1 \\ & \Phi & \ddots & & & \mathrm{P} \; \vdots & & \\ \phi_{N,1} & \phi_{N,2} & & \phi_{N,N} & x_N & y_N & z_N & 1 \end{array}\right] \begin{bmatrix} w_1 \\ w_2 \\ \mathbf{w} \; \vdots \\ w_N \\ a \\ b \\ \mathbf{c} \; c \\ d \end{bmatrix} = \begin{bmatrix} f_1 \\ f_2 \\ \mathbf{f} \; \vdots \\ f_N \end{bmatrix}$$

4 unknowns a, b, c, d added ➔ 4 new constraints needed

Additional constraints: reproduction of all linear functions

- "If all data points $(\mathbf{x}_i,\ f_i)$ are sampled from a linear function, RBF should reproduce the original function"

- Additional constraints:
  - $\sum_{i=1}^{N} w_i = 0$
  - $\sum_{i=1}^{N} x_i w_i = 0$
  - $\sum_{i=1}^{N} y_i w_i = 0$
  - $\sum_{i=1}^{N} z_i w_i = 0$

$$
\left[\begin{array}{cccc|cccc}
\phi_{1,1} & \phi_{1,2} & & \phi_{1,N} & x_1 & y_1 & z_1 & 1 \\
\phi_{2,1} & \phi_{2,2} & & \phi_{2,N} & x_2 & y_2 & z_2 & 1 \\
 & & \ddots & & & \vdots & & \\
\phi_{N,1} & \phi_{N,2} & & \phi_{N,N} & x_N & y_N & z_N & 1 \\
\hline
x_1 & x_2 & & x_N & 0 & 0 & 0 & 0 \\
y_1 & y_2 & \cdots & y_N & 0 & 0 & 0 & 0 \\
z_1 & z_2 & & y_N & 0 & 0 & 0 & 0 \\
1 & 1 & & 1 & 0 & 0 & 0 & 0
\end{array}\right]
\begin{bmatrix} w_1 \\ w_2 \\ \vdots \\ w_N \\ a \\ b \\ c \\ d \end{bmatrix}
=
\begin{bmatrix} f_1 \\ f_2 \\ \vdots \\ f_N \\ 0 \\ 0 \\ 0 \\ 0 \end{bmatrix}
$$

Φ $\quad$ P $\quad$ $\mathrm{P}^\intercal$ $\quad$ $\mathbf{w}$ $\quad$ $\mathbf{c}$ $\quad$ $\mathbf{f}$

Introducing gradient constraints

- Introduce weighted sum of basis' gradient $\boldsymbol{\nabla}\phi$:

$$f(\mathbf{x}) = \sum_{i=1}^{N} \left\{ w_i \phi(\mathbf{x} - \mathbf{x}_i) + \mathbf{v}_i^\mathsf{T} \boldsymbol{\nabla}\phi(\mathbf{x} - \mathbf{x}_i) \right\} + ax + by + cz + d$$

- Gradient of f :

$$\boldsymbol{\nabla} f(\mathbf{x}) = \sum_{i=1}^{N} \{ w_i \boldsymbol{\nabla}\phi(\mathbf{x} - \mathbf{x}_i) + \mathrm{H}\phi(\mathbf{x} - \mathbf{x}_i)\mathbf{v}_i \} + \begin{bmatrix} a \\ b \\ c \end{bmatrix}$$

- Incorporate gradient constraints $\boldsymbol{\nabla} f(\mathbf{x}_i) = \mathbf{n}_i$

$$\mathrm{H}\phi = \begin{pmatrix} \phi_{\mathrm{xx}} & \phi_{\mathrm{xy}} & \phi_{\mathrm{xz}} \\ \phi_{\mathrm{yx}} & \phi_{\mathrm{yy}} & \phi_{\mathrm{yz}} \\ \phi_{\mathrm{zx}} & \phi_{\mathrm{zy}} & \phi_{\mathrm{zz}} \end{pmatrix}$$

Hessian matrix

Hermite Radial Basis Functions Implicits [Macedo CGF10]

Introducing gradient constraints

- 1^{st} data point:

Value constraint:

$$f(\mathbf{x}_1) = w_1\phi_{1,1} + \mathbf{v}_1^\intercal \nabla\phi_{1,1} + w_2\phi_{1,2} + \mathbf{v}_2^\intercal \nabla\phi_{1,2} + \cdots + w_N\phi_{1,N} + \mathbf{v}_N^\intercal \nabla\phi_{1,N}$$

$$by_1 + cz_1 + d = f_1$$

Gradient constraint:

$$\nabla f(\mathbf{x}_1) = w_1\nabla\phi_{1,1} + \mathrm{H}\phi_{1,1}\mathbf{v}_1 + w_2\nabla\phi_{1,2} + \mathrm{H}\phi_{1,2}\mathbf{v}_2 + \cdots + w_N\nabla\phi_{1,N} + \mathrm{H}$$

$$\begin{bmatrix} a \\ b \\ c \end{bmatrix} = \mathbf{n}_1$$

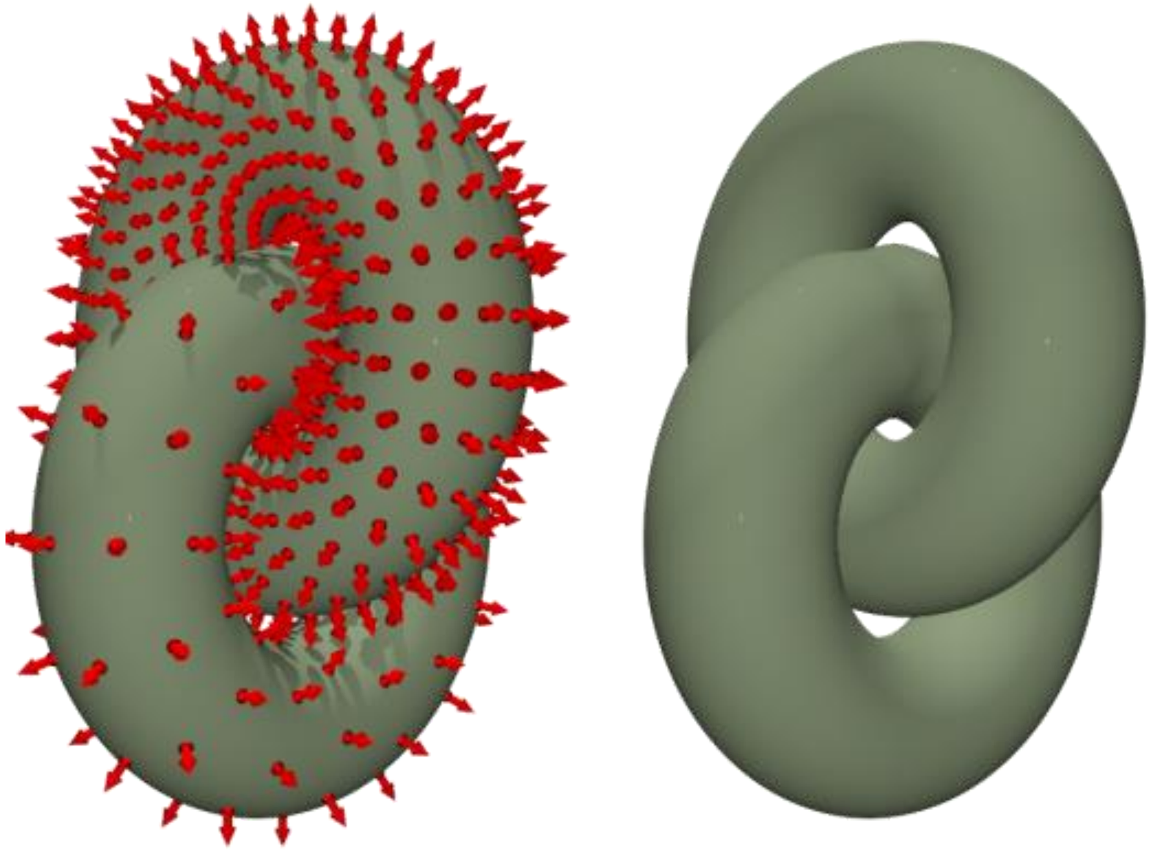
$$\begin{bmatrix} \Phi_{1,1} & \Phi_{1,2} & \cdots & \Phi_{1,N} & \mathrm{P}_1 \end{bmatrix} \begin{bmatrix} w_1 \\ \mathbf{v}_1 \\ w_2 \\ \mathbf{v}_2 \\ \vdots \\ w_N \\ \mathbf{v}_N \\ a \\ b \\ c \\ d \end{bmatrix} = \begin{bmatrix} f_1 \\ \mathbf{n}_1 \end{bmatrix}$$

$$\Phi_{1,1} = \begin{bmatrix} \phi_{1,1} & (\nabla\phi_{1,1})^\intercal \\ \nabla\phi_{1,1} & \mathrm{H}\phi_{1,1} \end{bmatrix}, \quad \Phi_{1,2} = \begin{bmatrix} \phi_{1,2} & (\nabla\phi_{1,2})^\intercal \\ \nabla\phi_{1,2} & \mathrm{H}\phi_{1,2} \end{bmatrix}, \quad \Phi_{1,N} = \begin{bmatrix} \phi_{1,N} & (\nabla\phi_{1,N})^\intercal \\ \nabla\phi_{1,N} & \mathrm{H}\phi_{1,N} \end{bmatrix}, \quad \mathrm{P}_1 = \begin{bmatrix} x_1 & y_1 & z_1 & 1 \\ 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix}$$

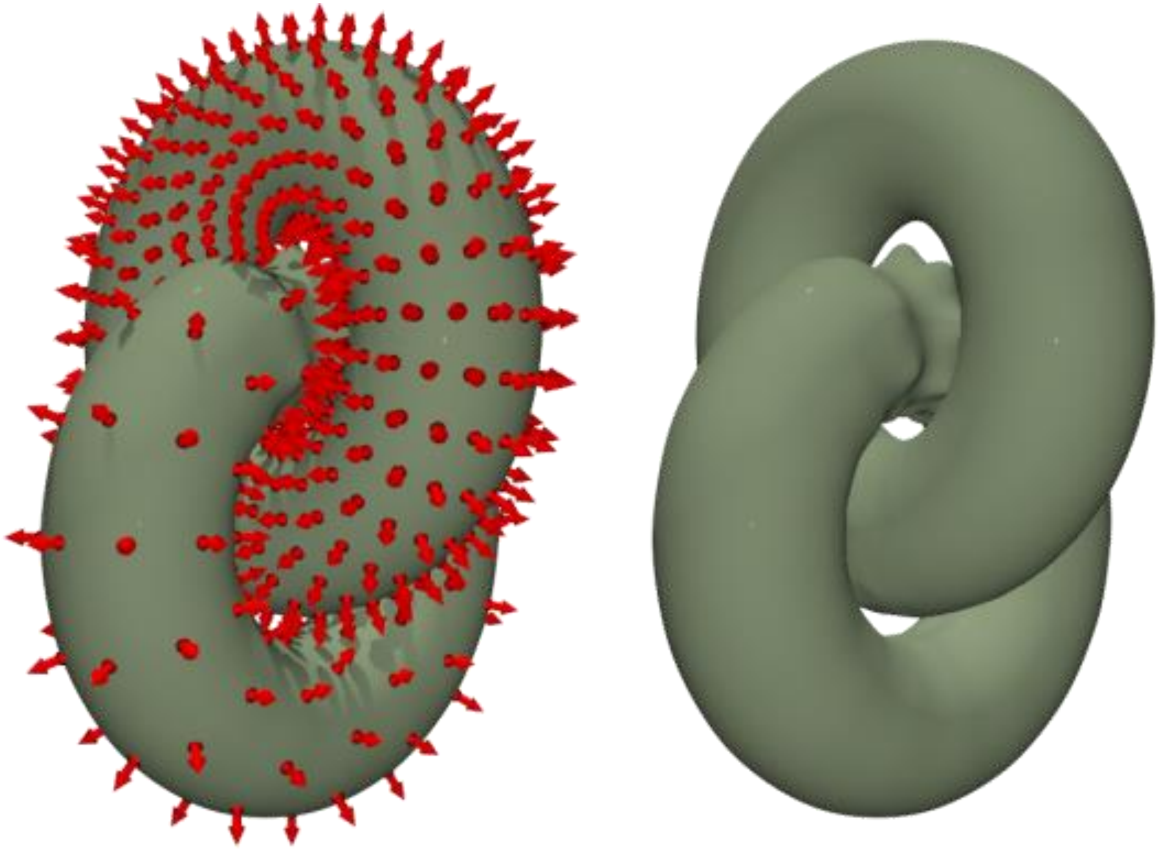
Hermite Radial Basis Functions Implicits [Macedo CGF10]

$$
\begin{bmatrix}
\Phi_{1,1} & \Phi_{1,2} & \cdots & \Phi_{1,N} & \mathrm{P}_1 \\
\Phi_{2,1} & \Phi_{2,2} & & \Phi_{2,N} & \mathrm{P}_2 \\
\vdots & & \ddots & \vdots & \\
\Phi_{N,1} & \Phi_{N,2} & & \Phi_{N,N} & \mathrm{P}_N \\
P_1^\intercal & P_2^\intercal & \cdots & P_N^\intercal & \begin{matrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{matrix}
\end{bmatrix}
\begin{bmatrix}
w_1 \\ \mathbf{v}_1 \\ w_2 \\ \mathbf{v}_2 \\ \vdots \\ w_N \\ \mathbf{v}_N \\ a \\ b \\ c \\ d
\end{bmatrix}
=
\begin{bmatrix}
f_1 \\ \mathbf{n}_1 \\ f_2 \\ \mathbf{n}_2 \\ \vdots \\ f_N \\ \mathbf{n}_N \\ 0 \\ 0 \\ 0 \\ 0
\end{bmatrix}
$$

Comparison



Gradient constraints



Simple offsetting with
value constraints only

References

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- A survey of methods for moving least squares surfaces [Cheng PBG08]

- Scattered Data Interpolation for Computer Graphics [Anjyo SIGGRAPH14 Course]

- An as-short-as-possible introduction to the least squares, weighted least squares and moving least squares for scattered data approximation and interpolation [Nealen TechRep04]

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