

# Notes on Unified-EPA (UEPA)

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Unified-EPA combines the GJK (Gilbert–Johnson–Keerthi) algorithm and the EPA (Expanding polytope algorithm). The algorithm operates on the Minkowski sum (difference) of two convex shapes. For non-intersecting shapes it returns the closest distance. For intersecting shapes it returns the penetration depth which is defined by the minimal displacement needed to separate these shapes. It also returns two corresponding points, compare Figure 1.

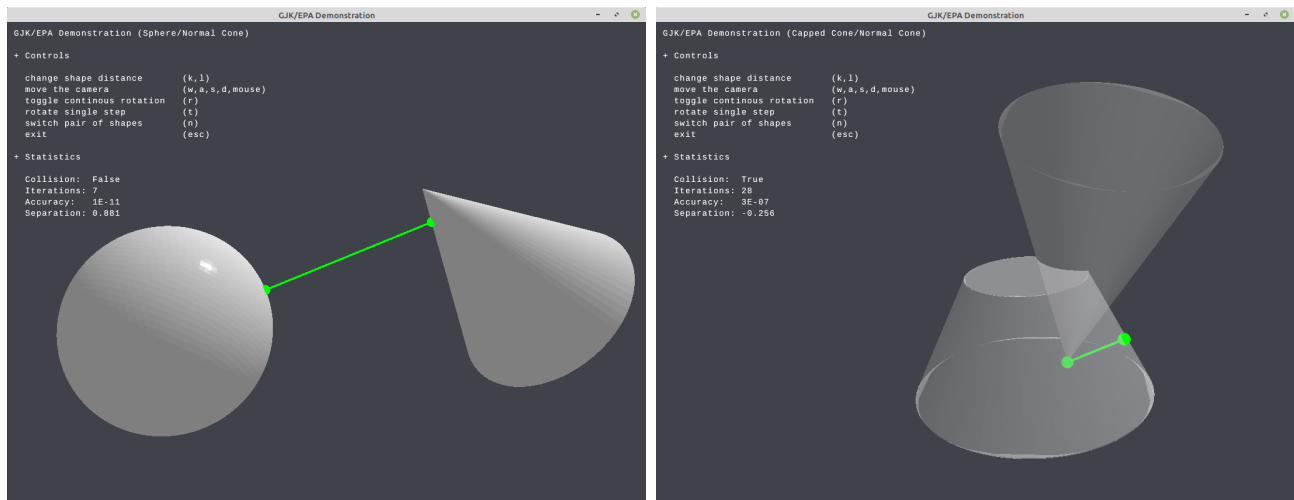


Figure 1: Demo implementation of the unified-EPA algorithm. Left: Separated shapes. Right: Intersecting shapes. Separating vector shown as green line.

The collision information can be derived from the knowledge of the relative position of the origin to the Minkowski difference ( $M_d$ ) of the two shapes: the shapes are colliding if the origin is contained within the  $M_d$ , otherwise they are separated. For both cases the separation (and the separation vector) can be determined by finding the smallest distance of the origin to the surface of the  $M_d$ .

The  $M_d$  is defined by means of support functions. The algorithm described on the next page constructs a polytope within the implicitly defined  $M_d$  to extract the information about the relative position of the  $M_d$  to the origin.

## Demo implementation

[https://github.com/notgiven688/unified\\_epa](https://github.com/notgiven688/unified_epa)

Outlined below are the steps of the UEPA algorithm for an example case in two dimensions (see Figure 2):

- (a) The Md is outlined in black. In this example the origin (red cross) lies within the Md. Blue cross: point known to be deep within the Md. A small initial triangle (the starting polytope) is created around this point. It is guaranteed that the triangle (tetrahedron in 3d) lies within the Md.
- (b) The point of closest distance (green cross) from the polytope to the origin is found. The support point (green circle) of the Md is found by searching in the negative direction of the position vector of the closest point, i.e. the search direction (green arrow) points from the green cross to the red cross.
- (c) The polytope (outlined in blue) was expanded by adding the newly found support point (green circle). Note that the expansion is done in such a way that the resulting polytope is convex. In the example here, two edges of the initial triangle got replaced.
- (d) Step (b) is repeated.
- (e) Step (c) is repeated. Note that from now on the origin is enclosed by the polytope.
- (f) Step (b) is repeated with a twist: The search direction is reversed, i.e. the green direction vector points from the red cross to the green cross. This is done when the origin is already enclosed by the polytope.
- (g) Step (c) is repeated.
- (h) Step (b) is repeated. However the found support point is already known and we can not further expand the closest edge (light green line) of the polytope. This edge must be the closest to the origin. We terminate the algorithm here.

Additional notes:

- A point deep within the Md can be found by subtracting the center of mass of both shapes.
- Some numerical stability of the algorithm originates from the finite volume of the initial triangle (tetrahedron). The size of the initial polytope is an upper bound of how small the Md of shapes can be.
- If the origin is outside the Md the algorithm reduces to GJK.
- Once the origin is enclosed by the polytope the algorithm reduces to EPA.
- Once the origin is enclosed it is sufficient to rely on line-point (plane-point in 3d) calculations to determine the closest point of the polytope to the origin, instead of using segment-point (triangle-point in 3d) calculations.

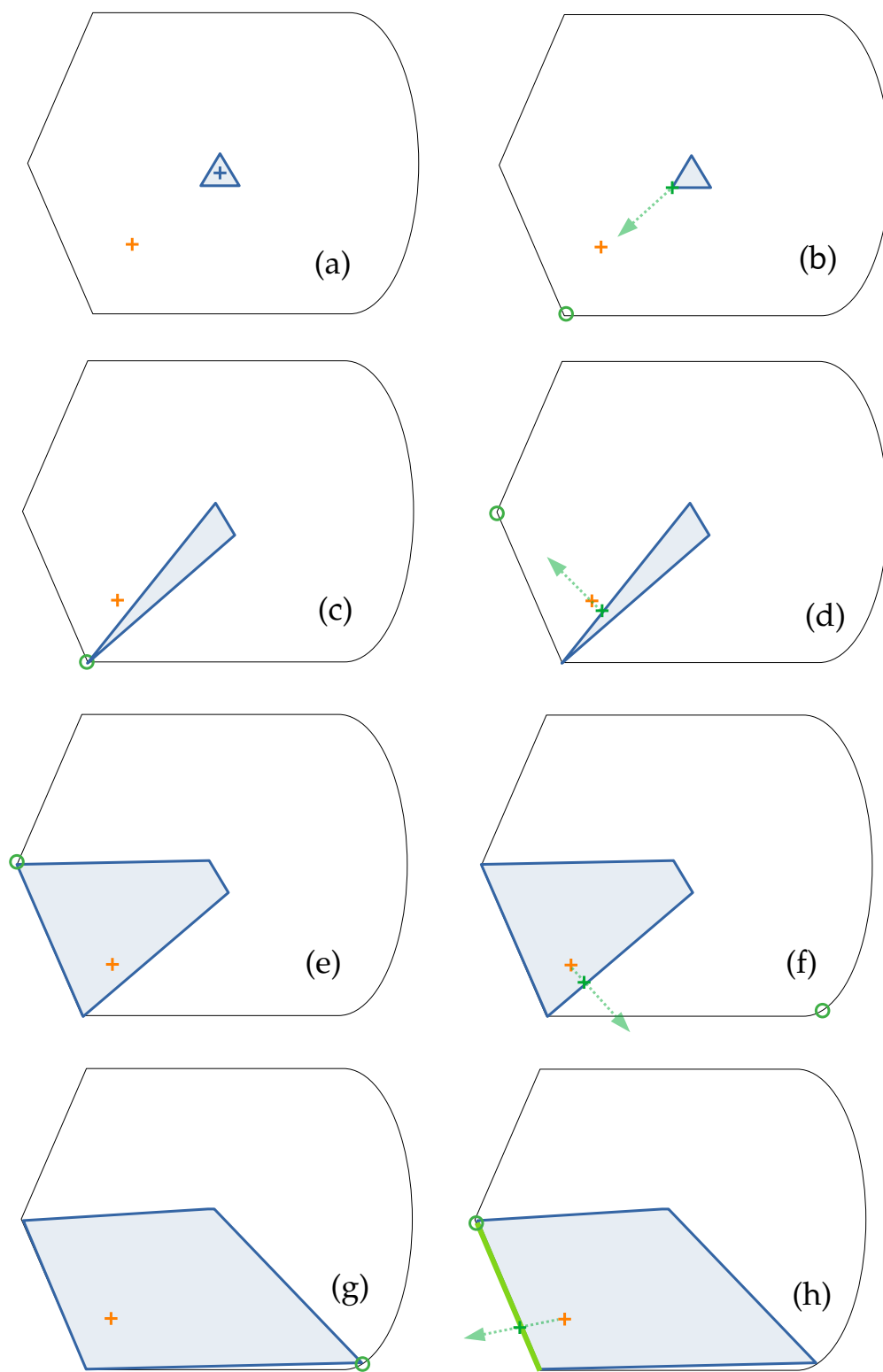


Figure 2: Steps of the unified EPA algorithm. In this example the algorithm converges after four calls to the support function.