

# Discrete differential geometry of surfaces. Variational principles, algorithms, and implementation

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# 1 Introduction

## Part I

# Discrete Uniformization

## 2 Discrete Uniformization

### 2.1 Discrete conformal equivalence

**Definition 1.** Two Euclidean triangulations  $T$  and  $\tilde{T}$  are discretely conformally equivalent if there is a map  $u : V \rightarrow \mathbb{R}$  such that for any edge  $ij$  it is

$$l_{ij} = e^{u_i + u_j} \tilde{l}_{ij}$$

where  $l_{ij}$  is the length of the edge  $ij$ .

**Definition 2.** A discrete flat Euclidean metric is a map  $l : E \rightarrow \mathbb{R}_+$  such that triangle inequalities are satisfied and angle sums around each inner vertex are equal to  $2\pi$ .

### 2.2 Variational principles for discrete metrics in $\mathbb{E}^2$ , $\mathbb{H}^2$ , and $\mathbb{S}^2$

Construction of discrete flat metrics. A discrete Euclidean flat metric is the minimizer of a convex functional.

$$\lambda_{ij} := 2 \log l_{ij} \tag{1}$$

$$\tilde{\lambda}_{ij} := \lambda_{ij} + u_i + u_j \tag{2}$$

$$f_{Euc}(u_i, u_j, u_k) := \alpha_i \tilde{\lambda}_{jk} + \alpha_j \tilde{\lambda}_{ki} + \alpha_k \tilde{\lambda}_{ij} + 2(\mathcal{I}(\alpha_i) + \mathcal{I}(\alpha_j) + \mathcal{I}(\alpha_k)) \tag{3}$$

**Definition 3.**

$$E_{Euc}(u) := \sum_{ijk \in F} \left( f_{Euc}(u_i, u_j, u_k) - \frac{\pi}{2} (\tilde{\lambda}_{jk} + \tilde{\lambda}_{ki} + \tilde{\lambda}_{ij}) \right) + \sum_{i \in V} \Theta_i u_i \tag{4}$$

This definition and the derivatives can be found in [BPS10]

For the hyperbolic case  $\lambda$  and  $\tilde{\lambda}$  are defined as before. Further define

$$\beta_i := \frac{1}{2} (\pi + \alpha_i - \alpha_j - \alpha_k) \tag{5}$$

$$\beta_j := \frac{1}{2} (\pi - \alpha_i + \alpha_j - \alpha_k) \tag{6}$$

$$\beta_k := \frac{1}{2} (\pi - \alpha_i - \alpha_j + \alpha_k) \tag{7}$$

$$f_{Hyp}(u_i, u_j, u_k) := \beta_i \tilde{\lambda}_{jk} + \beta_j \tilde{\lambda}_{ki} + \beta_k \tilde{\lambda}_{ij} \tag{8}$$

$$+ \mathcal{I}(\alpha_i) + \mathcal{I}(\alpha_j) + \mathcal{I}(\alpha_k) + \mathcal{I}(\beta_i) + \mathcal{I}(\beta_j) + \mathcal{I}(\beta_k) \tag{9}$$

$$+ \mathcal{I} \left( \frac{1}{2} (\pi - \alpha_i - \alpha_j - \alpha_k) \right) \tag{10}$$

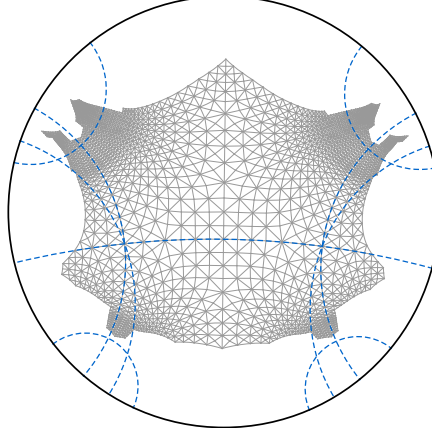


Figure 1: Hyperbolic flat metric on a genus 2 surface and the axes of the associated hyperbolic motions.

**Definition 4.**

$$E_{Hyp}(u) := \sum_{ijk \in F} \left( f_{Hyp}(u_i, u_j, u_k) - \frac{\pi}{2} (\tilde{\lambda}_{jk} + \tilde{\lambda}_{ki} + \tilde{\lambda}_{ij}) \right) + \sum_{i \in V} \Theta_i u_i \quad (11)$$

### 2.3 Realization

## 3 Uniformization of surfaces of higher genus

Triangulated surfaces of genus  $g \geq 2$  without boundary can be equipped with a discretely conformally equivalent flat hyperbolic metric [BPS10]. By flat hyperbolic metric we mean that the edge lengths are hyperbolic and for any vertex the angle sum is  $2\pi$ . To realize this metric in the hyperbolic plane e.g. in the Poincaré disk model one has to introduce cuts along a basis of the homotopy. This creates a simply connected domain in  $\mathbb{H}^2$ . Matching cut paths are related by a hyperbolic motion i.e. the Möbius transformations that leave the unit disk invariant (Figure 1).

### 3.1 The cut-graph and fuchsian groups

*Want to say here: the number of transformations generated by the mapping of corresponding edges equals the number of path segments in the homotopy-cut-graph. They generate a fuchsian group with #vertices relations*

**Proposition 1.**

**3.2 Minimal presentation****4 Canonical fundamental domains of fuchsian groups****4.1 Separated handles****4.2 Opposite sides identified****5 Uniformization of tori****5.1 Elliptic Functions****5.2 The modul space****5.3 Numerical convergence analysis****5.4 The modulus of the Wente torus****6 Uniformization of hyperelliptic surfaces****6.1 Construction**

Any hyperelliptic Riemann surface can be expressed as an algebraic curve of the form

$$\mu^2 = \prod_{i=1}^n (\lambda - \lambda_i)^2 \quad n \geq 3, \quad \lambda_i \neq \lambda_j \forall i \neq j.$$

Here  $\lambda_i$  are the branch points of the doubly covered Riemann sphere.

**6.2 Weierstrass points on hyperelliptic surfaces**

A hyperelliptic surface comes together with a holomorphic involution  $h$  called the hyperelliptic involution. The branch points are fixed points under this transformation. For a hyperelliptic algebraic curve it is  $h(\mu, \lambda) = (-\mu, \lambda)$

**6.3 Canonical domains****6.4 Lawsons surface****7 Conformal Mapping to  $\hat{\mathbb{C}}$  (Planned)****7.1 Selection of Branch Data****7.2 Examples****8 Simply and multiply connected domains****8.1 Variation of edge length****8.2 Examples****8.3 Comparison with Examples of the Schwarz-Christoffel community****Part II****Discrete Surface Parameterization****9 Discrete quasiisothermic parametrizations**

The notion of quasiconformal parameterizations



**9.1 Discrete quasiisothermic parameterizations****9.2 Formulation as boundary value problem****9.3 Global approach****9.4 Variational principle for S-isothermic surfaces****9.5 Constructing the associated family****9.6 A discrete ellipsoid and its dual surface****9.7 Applications in architecture****10 Gridshells and Applications in Architecture****11 References**

- [BPS10] Alexander I. Bobenko, Ulrich Pinkall, and Boris Springborn. Discrete conformal maps and ideal hyperbolic polyhedra. Preprint; <http://arxiv.org/abs/1005.2698>, 2010.