COMP3271 Computer Graphics

Transformation

2019-20

Objectives

Introduce the three fundamental transformations

- Translation
- Scaling
- Rotation

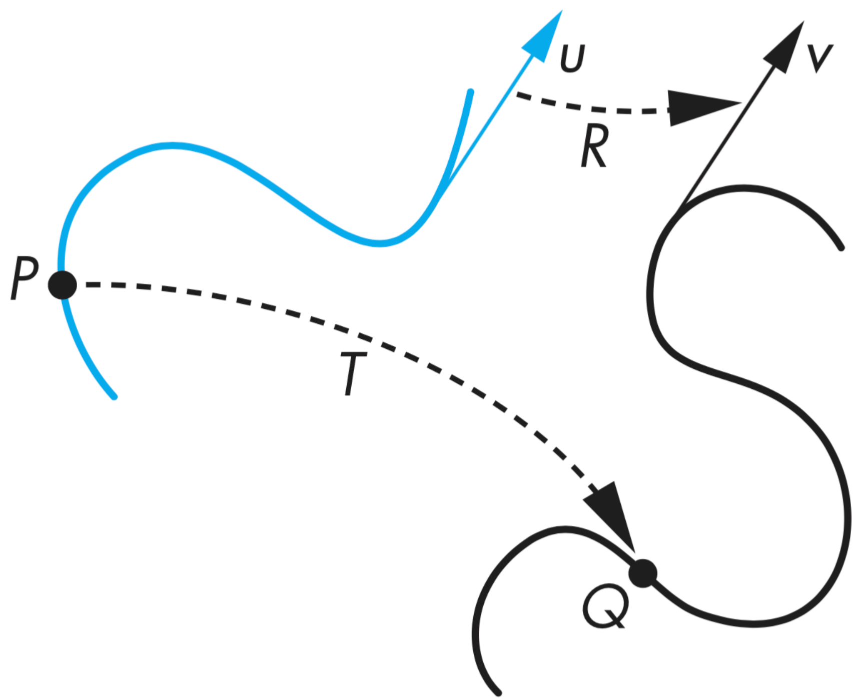
Derive homogeneous coordinate transformation matrices

Build arbitrary transformation from simple transformations

Materials adapted from textbook ppt and previous runs of the course

General Transformations

A transformation maps points to other points and/or vectors to other vectors



v=R(u)

Q=T(P)

Provides a mechanism to manipulate objects

Why Do We Need Transformations?

Makes modeling more convenient

- for example, often easier to generate models around origin
  - gluSphere() draws a sphere of radius r about the origin
- then move them to final position with transformations

Model viewing process via transformations

- projecting 3-D to 2-D will be done this way

Animation

- transformations as a function of time creates motion

A demo: https://processing.org/examples/tree.html

Linear Algebra (very quick review)

A linear combination of two vectors v and w is given by α v + β w, where α and are β scalars.

A **basis** for a space is a linearly independent set of vectors whose linear combinations include all vectors in the space, e.g., standard basis for 2-D plane:

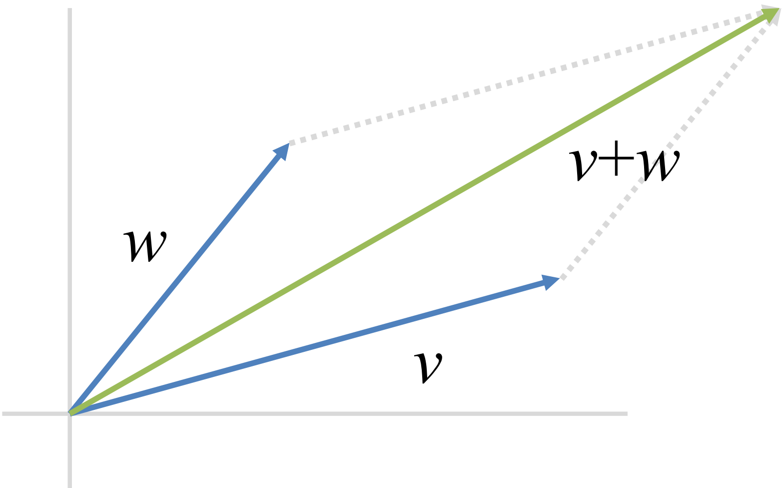
$$e_1 = \begin{pmatrix} 1 \\ 0 \end{pmatrix}, \quad e_2 = \begin{pmatrix} 0 \\ 1 \end{pmatrix}$$

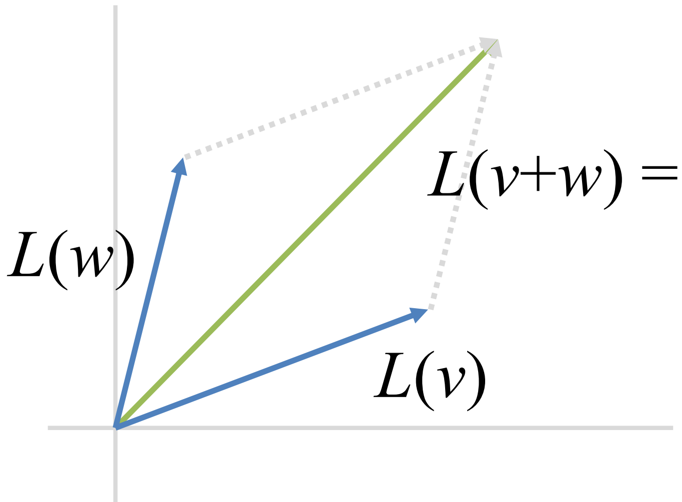
There are infinitely many possible bases.

Linear Transformation

A transformation (or mapping) L is linear when given any two vectors v and $w \in R^n$,

- $L(v + w) = L(v) + L(w)$
- $L(kv) = k\,L(v)$ for some scalar k





Linear Transformation

Considering the Cartesian coordinates, where a vector $v = (x, y)^T$ is represented as a linear combination of the base vectors $e^1 = (1, 0)^T$ and $e^2 = (0, 1)^T$:

$$v = \begin{pmatrix} x \\ y \end{pmatrix} = x \begin{pmatrix} 1 \\ 0 \end{pmatrix} + y \begin{pmatrix} 0 \\ 1 \end{pmatrix}$$

Applying a linear transformation to v:

$$L(\begin{pmatrix} x \\ y \end{pmatrix}) = L(x \begin{pmatrix} 1 \\ 0 \end{pmatrix} + y \begin{pmatrix} 0 \\ 1 \end{pmatrix}) = xL(\begin{pmatrix} 1 \\ 0 \end{pmatrix}) + yL(\begin{pmatrix} 0 \\ 1 \end{pmatrix})$$

Transformation of the base vectors

Linear Transformation

Linear transformations can be represented as **matrices**.

$$L(\begin{pmatrix} x \\ y \end{pmatrix}) = L(x\begin{pmatrix} 1 \\ 0 \end{pmatrix} + y\begin{pmatrix} 0 \\ 1 \end{pmatrix}) = xL(\begin{pmatrix} 1 \\ 0 \end{pmatrix}) + yL(\begin{pmatrix} 0 \\ 1 \end{pmatrix})$$

$$= \underbrace{\begin{bmatrix} L(\begin{pmatrix} 1 \\ 0 \end{pmatrix}) L(\begin{pmatrix} 0 \\ 1 \end{pmatrix}) \end{bmatrix}}_{\text{A 2x2 matrix}} \begin{pmatrix} x \\ y \end{pmatrix}$$

Affine Transformation

Affine transformation takes a more general form of

$$A(v) = Lv + b$$

where matrix L represents a non-singular linear transformation (i.e., $\det(L) \neq 0$) and b is a vector.

It can be viewed as a linear transformation plus a translation

Affine Transformations

Preserve geometric properties such as:

- Collinearity (lines remain lines under transformation)
- Parallelism
- Ratios of distances (e.g., mid-points remain mid-points)

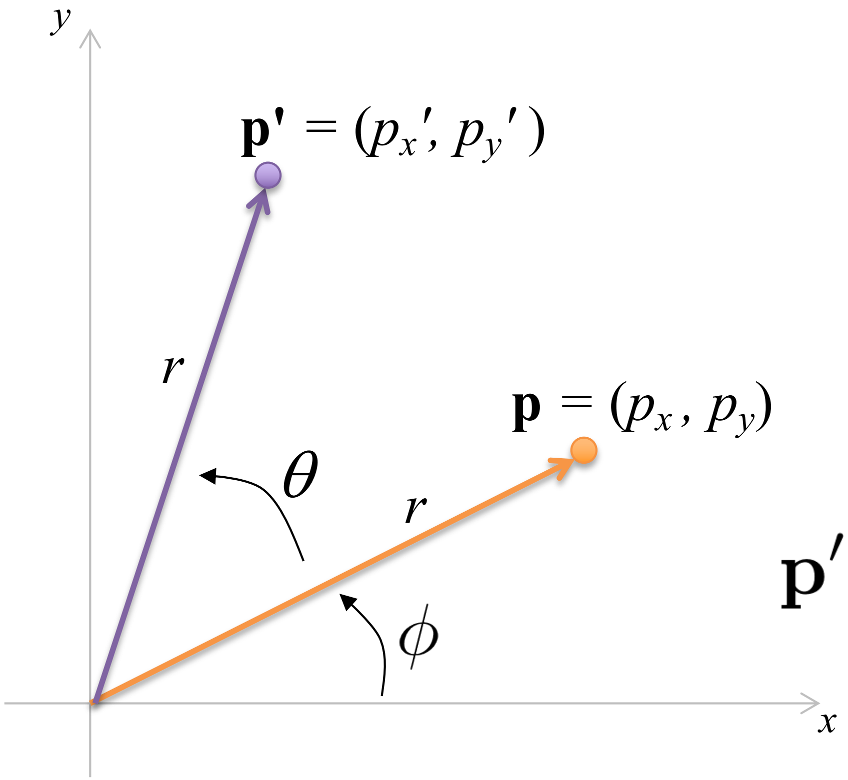
Characteristic of many physically important transformations

- Rigid body transformations: rotation, translation
- Scaling, shear

Importance in graphics: we need only transform endpoints of line segments and let implementation draw line segment between the transformed endpoints

2D Rotation

$$p_x = r\cos\phi,\ \ p_y = r\sin\phi$$
$$p'_x = r\cos(\phi+\theta) = r\cos\phi\cos\theta - r\sin\phi\sin\theta$$
$$p'_y = r\sin(\phi+\theta) = r\sin\phi\cos\theta + r\cos\phi\sin\theta$$



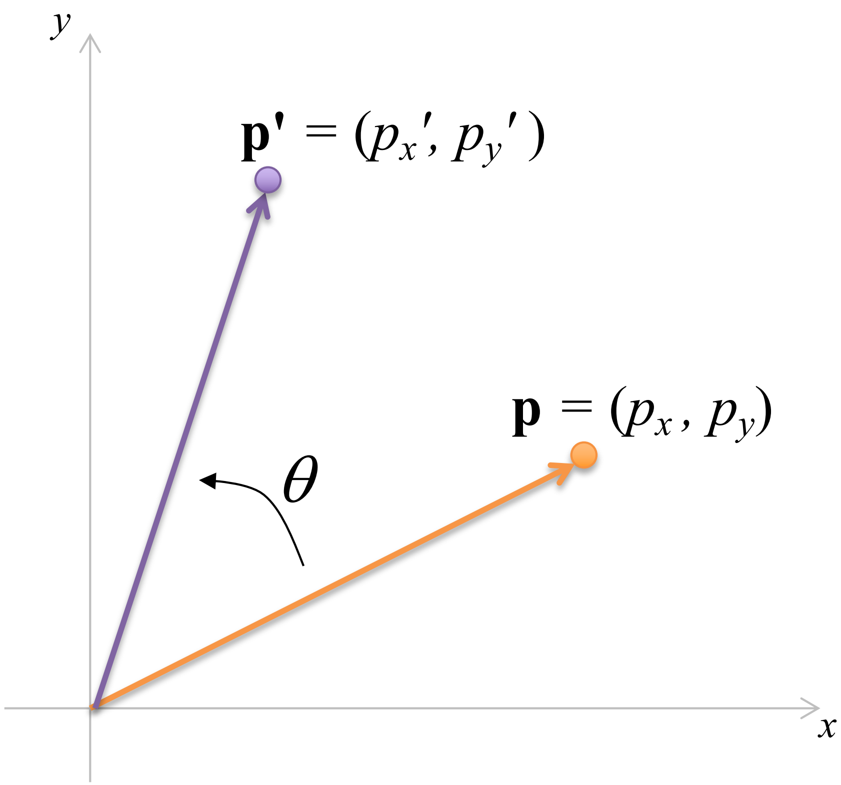
$$p'_x = p_x\cos\theta - p_y\sin\theta$$
$$p'_y = p_x\sin\theta + p_y\cos\theta$$

$$\mathbf{p}' = \begin{pmatrix} p'_x \\ p'_y \end{pmatrix} = \begin{pmatrix} p_x\cos\theta - p_y\sin\theta \\ p_x\sin\theta + p_y\cos\theta \end{pmatrix}$$

2D Rotation

$$\mathbf{p}' = \begin{pmatrix} p'_x \\ p'_y \end{pmatrix} = \begin{pmatrix} p_x \cos\theta - p_y \sin\theta \\ p_x \sin\theta + p_y \cos\theta \end{pmatrix}$$

$$= \begin{pmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{pmatrix} \begin{pmatrix} p_x \\ p_y \end{pmatrix}$$

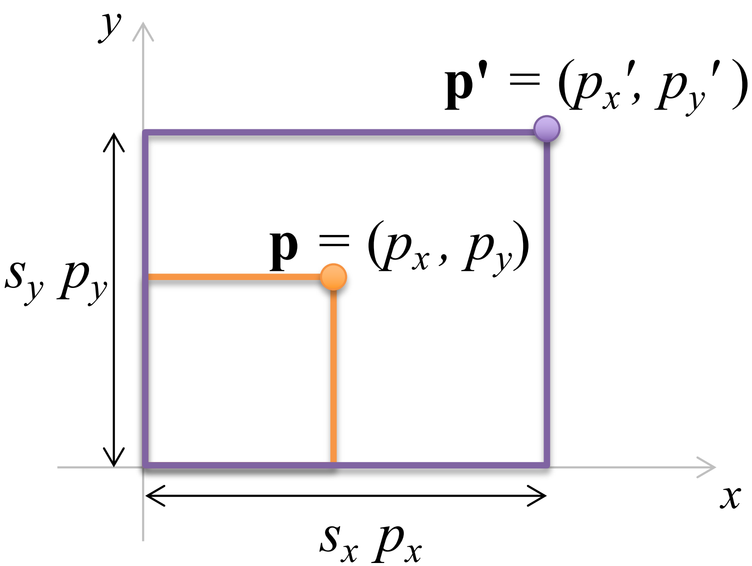


$$\mathbf{p}' = \underbrace{\mathbf{R}(\theta)}_{\text{rotation}}\mathbf{p}$$

Note that the rotation is about the origin

2D Scaling

$$\begin{pmatrix} p'_x \\ p'_y \end{pmatrix} = \begin{pmatrix} s_x p_x \\ s_y p_y \end{pmatrix} = \begin{pmatrix} s_x & 0 \\ 0 & s_y \end{pmatrix} \begin{pmatrix} p_x \\ p_y \end{pmatrix}$$

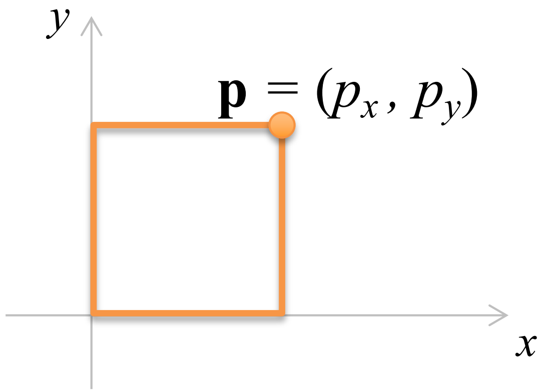


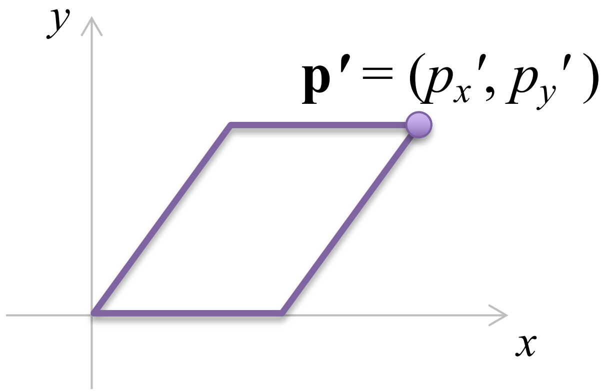
$$\mathbf{p}' = \underbrace{\mathbf{S}(s_x, s_y)}_{\text{scaling}}\mathbf{p}$$

We have a uniform scaling if $s_x = s_y$

2D Shearing

X-Shear

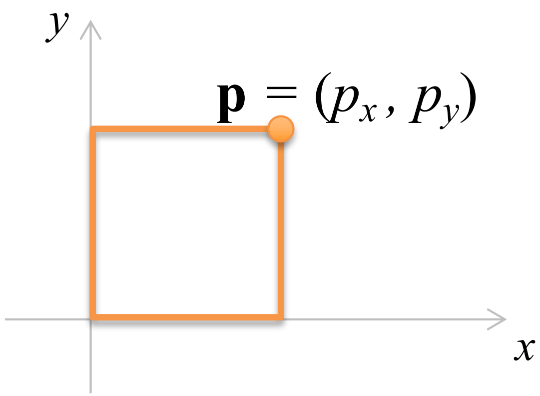


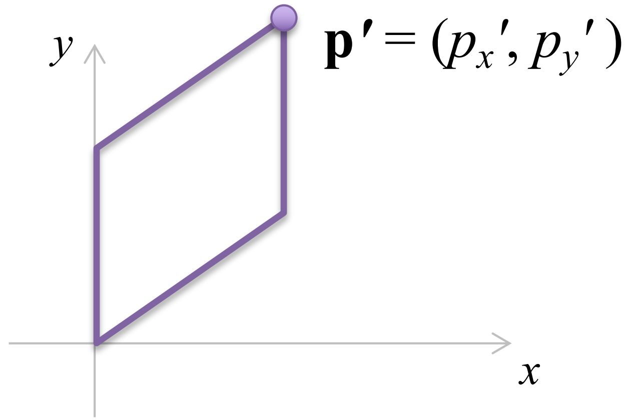


$$\begin{pmatrix} p'_x \\ p'_y \end{pmatrix} = \begin{pmatrix} p_x + m p_y \\ p_y \end{pmatrix} = \begin{pmatrix} 1 & m \\ 0 & 1 \end{pmatrix} \begin{pmatrix} p_x \\ p_y \end{pmatrix}$$

$$\mathbf{p}' = \underbrace{\mathbf{Sh}_x(m)}_{\text{shearing}}\mathbf{p}$$

Y-Shear



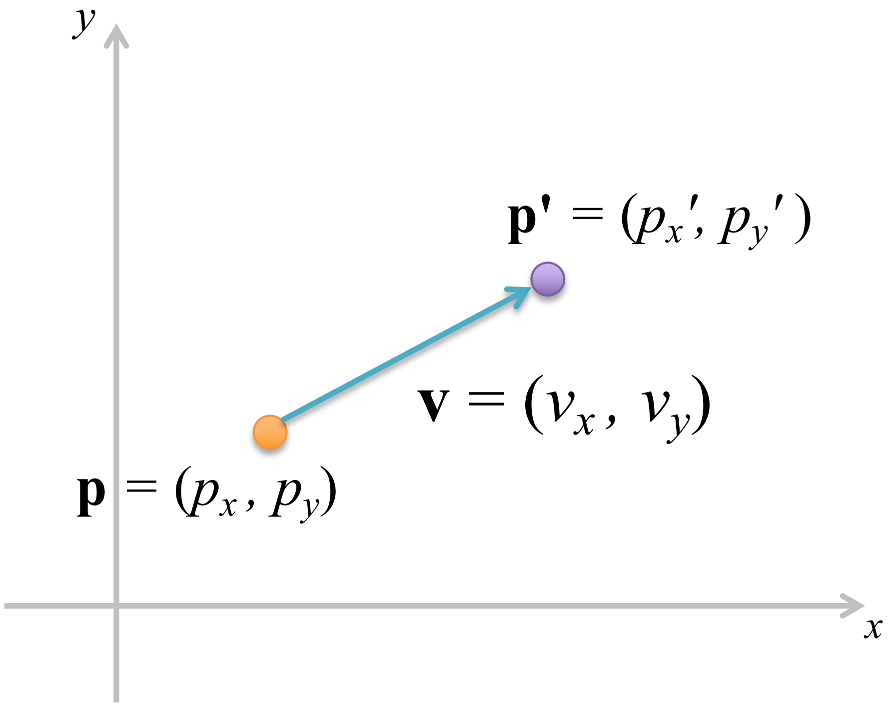


$$\begin{pmatrix} p'_x \\ p'_y \end{pmatrix} = \begin{pmatrix} p_x \\ m p_x + p_y \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ m & 1 \end{pmatrix} \begin{pmatrix} p_x \\ p_y \end{pmatrix}$$

$$\mathbf{p}' = \underbrace{\mathbf{Sh}_y(m)}_{\text{shearing}}\mathbf{p}$$

2D Translation

$$\begin{pmatrix} p'_x \\ p'_y \end{pmatrix} = \begin{pmatrix} p_x \\ p_y \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} = \begin{pmatrix} p_x + v_x \\ p_y + v_y \end{pmatrix}$$



$$\mathbf{p}' = \underbrace{\mathbf{p} + \mathbf{v}}_{\text{translation}}$$

The Basic Transformations

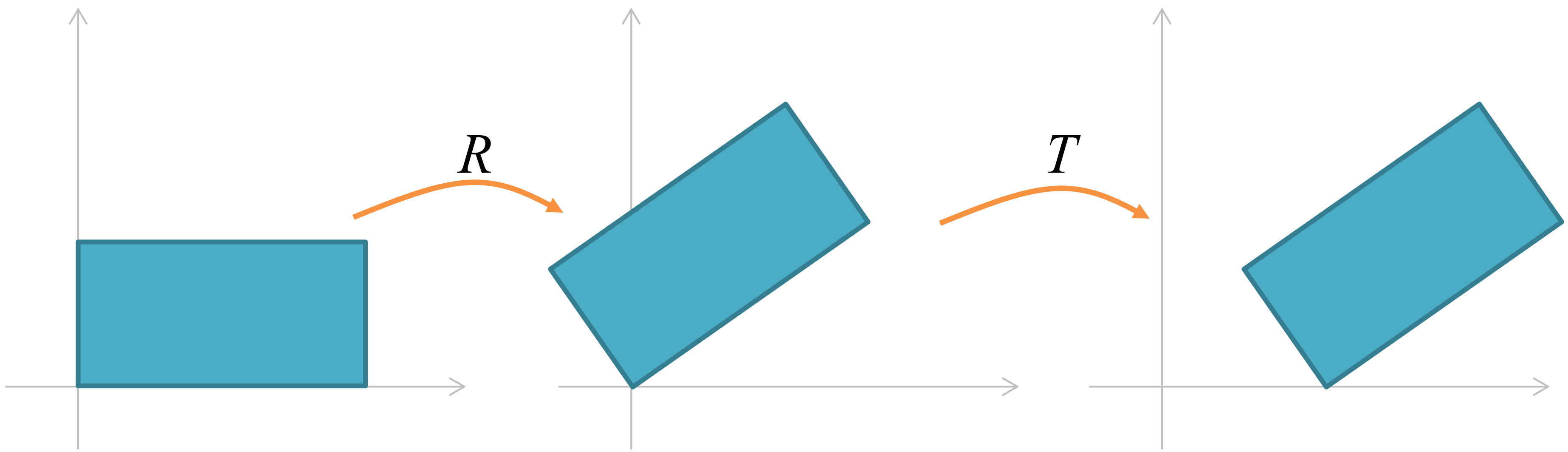
Rotation	$\mathbf{p}' = \mathbf{R}(\theta)\mathbf{p}$
Scaling	$\mathbf{p}' = \mathbf{S}(s_x, s_y)\mathbf{p}$
Shearing	$\mathbf{p}' = \mathbf{Sh}_x(m)\mathbf{p} \quad \mathbf{p}' = \mathbf{Sh}_y(m)\mathbf{p}$
Translation	$\mathbf{p}' = \mathbf{p} + \mathbf{v}$

- can represent any affine transformation as a sequence of these 4
- A general rotation / scaling / shearing transformation has exactly one fixed point.
- A translation has no fixed point
- $\det(L) \neq 0$ is the scale factor of the area of a transformed region by the affine transformation
- A 2D affine transformation is uniquely determined by correspondences between three pairs of non-collinear points

Composition of Transformations

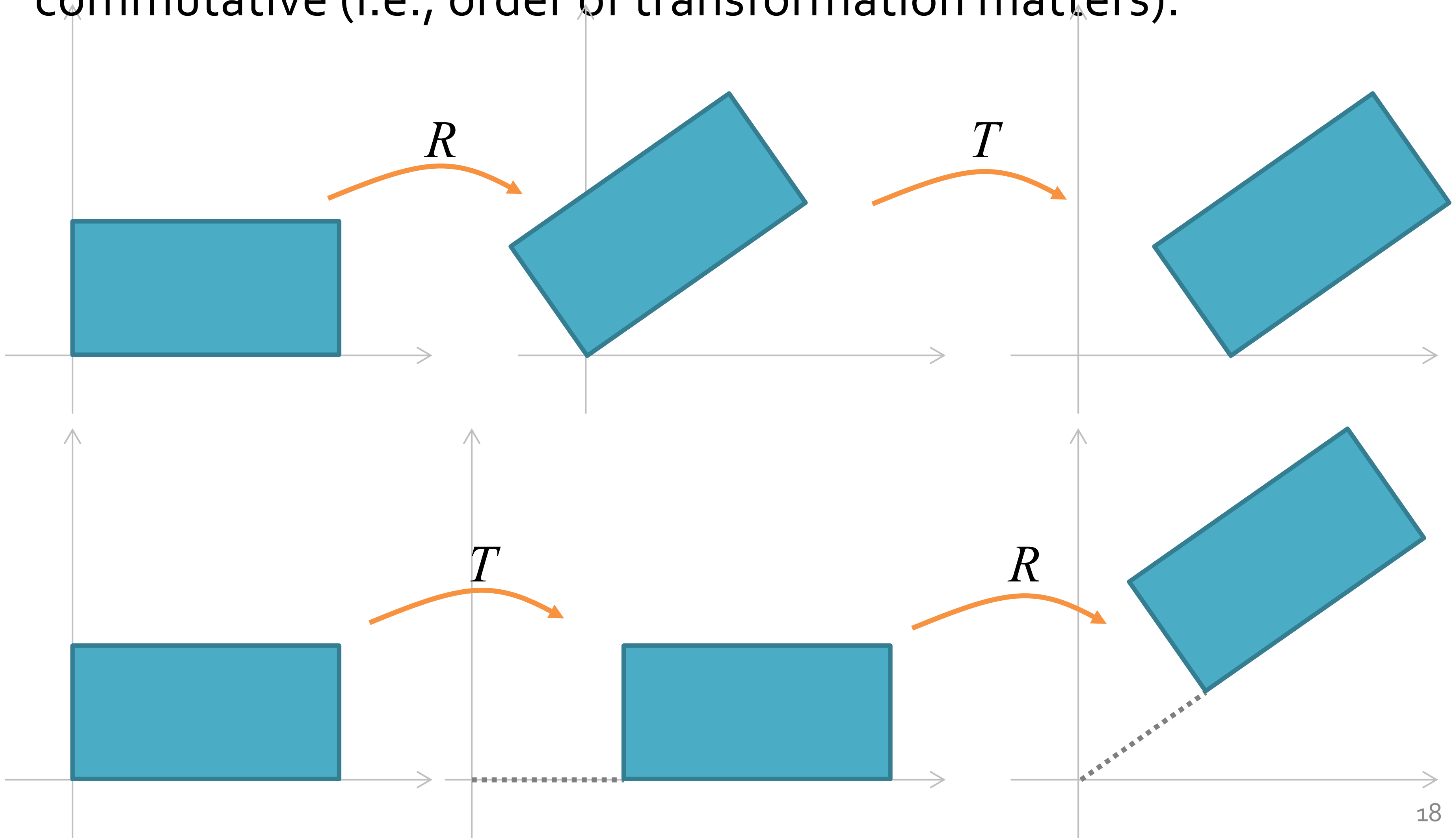
The composition of two affine transformation is also an affine transformation

Example: a rotation R followed by a translation T



Composition of Transformations

In general, the composition of affine transformations is non-commutative (i.e., order of transformation matters).



Matrix Compositions

Suppose we want to first rotate a point by $\mathbf{R}_1$, then scale by $\mathbf{S}$, then rotate again by $\mathbf{R}_2$, we have:

$$\mathbf{p}' = \underline{\mathbf{R}_2 \cdot \mathbf{S} \cdot \mathbf{R}_1}\, \mathbf{p} = \mathbf{M}\, \mathbf{p}$$

Transformation matrices are applied from right to left

Now, consider first rotate a point by $\mathbf{R}_1$, then translate by $\mathbf{v}$, then rotate again by $\mathbf{R}_2$, we have:

$$\mathbf{p}' = \mathbf{R}_2 \cdot (\mathbf{R}_1 \mathbf{p} + \mathbf{v}) = \mathbf{R}_2 \cdot \mathbf{R}_1 \mathbf{p} + \mathbf{R}_2 \mathbf{v}$$

Oops! We don't have a nice matrix composition by multiplication for the transformation because translation is not a linear transformation

Homogeneous Coordinates

A 2D point (x, y) is represented as (wx, wy, w), for any real number $w \neq 0$.

Therefore, any given point has infinitely many different homogeneous coordinate representations.

- Two points (wx, wy, w) and (ux, uy, u) in homogeneous coordinates are the same
- E.g.: the 2D points (4, 8, 2) and (20, 40, 10) are the same.

Conversely, given any homogeneous coordinates (x, y, w), $w \neq 0$, of a 2D point, the Cartesian coordinates of the point are given by $(x/w, y/w)$.

$$(x, y, w) \leftrightarrow (\frac{x}{w}, \frac{y}{w})$$

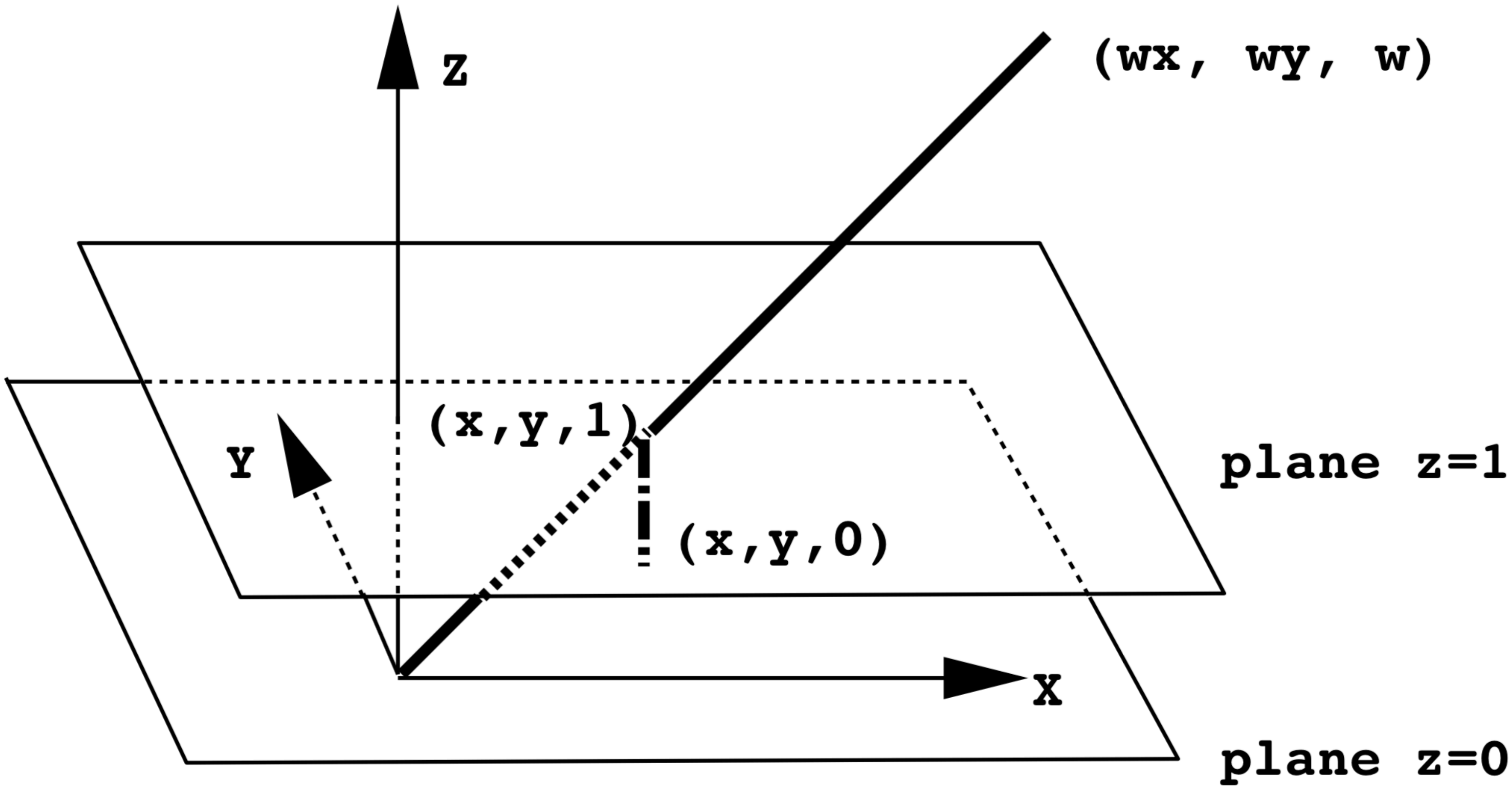
Homogeneous Coordinates

Homogeneous coordinates allow us to define points at infinity.

- $(0, 0, 0)$ does not represent a well-defined point
- When $x \neq 0$ or $y \neq 0$, $(x, y, 0)$ are the homogeneous coordinates of a point at infinity; in particular, $(x, y, 0)$ and $(-x, -y, 0)$ stand for the same point at infinity.
- A point at infinity indicates a direction and thus a 2D vector can be represented in homogeneous coordinates as $(x, y, 0)$.

Homogeneous Coordinates

A geometric interpretation



Reading: A.4 of online appendices: “Linear Algebra & Trigonometry” from the book “ Real-Time Rendering”

Homogeneous Representation of 2D Transformations

We represent 2D transformations using 3x3 matrices

Rotation

$$\mathbf{p}' = \mathbf{S}\mathbf{p}$$

$$\begin{pmatrix} p'_x \\ p'_y \\ 1 \end{pmatrix} = \begin{pmatrix} \cos\theta & -\sin\theta & 0 \\ \sin\theta & \cos\theta & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} p_x \\ p_y \\ 1 \end{pmatrix}$$

$$= \begin{pmatrix} p_x \cos\theta - p_y \sin\theta \\ p_x \sin\theta + p_y \cos\theta \\ 1 \end{pmatrix}$$

This is the same point as in slide 12

Homogeneous Representation of 2D Transformations

Scaling $\mathbf{p}' = \mathbf{S}\mathbf{p}$

$$\begin{pmatrix} p'_x \\ p'_y \\ 1 \end{pmatrix} = \begin{pmatrix} s_x & 0 & 0 \\ 0 & s_y & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} p_x \\ p_y \\ 1 \end{pmatrix} = \begin{pmatrix} s_x p_x \\ s_y p_y \\ 1 \end{pmatrix}$$

Translation $\mathbf{p}' = \mathbf{T}\mathbf{p}$

$$\begin{pmatrix} p'_x \\ p'_y \\ 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 & v_x \\ 0 & 1 & v_y \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} p_x \\ p_y \\ 1 \end{pmatrix} = \begin{pmatrix} p_x + v_x \\ p_y + v_y \\ 1 \end{pmatrix}$$

Now a translation can be represented as a matrix as well

Vector Transformations

Note that translation has no effect on vectors.

Translating a vector:

$$\begin{pmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} v_x \\ v_y \\ 0 \end{pmatrix} = \begin{pmatrix} v_x \\ v_y \\ 0 \end{pmatrix}$$

Translation has no effect

Composition of Transformations

With homogeneous transformations, composition of transformations can be represented by multiplication of matrices

Rotate, scale then rotate again

$$\mathbf{p}' = \underline{\mathbf{R}_2} \cdot \underline{\mathbf{S}} \cdot \underline{\mathbf{R}_1}\, \mathbf{p} = \underline{\mathbf{M}}\, \mathbf{p}$$

3x3 matrices for 2D transformations

Rotate, translate then rotate again

$$\mathbf{p}' = \mathbf{R}_2 \cdot \mathbf{T} \cdot \mathbf{R}_1\, \mathbf{p} = \mathbf{N}\, \mathbf{p}$$

3D Transformations

We represent 3D transformations using 4x4 matrices:

Rotation about x-axis

$$\mathbf{R}_x = \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & \cos\theta & -\sin\theta & 0 \\ 0 & \sin\theta & \cos\theta & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

Rotation about y-axis

$$\mathbf{R}_y = \begin{pmatrix} \cos\theta & 0 & \sin\theta & 0 \\ 0 & 1 & 0 & 0 \\ -\sin\theta & 0 & \cos\theta & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

Rotation about z-axis

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

Fixed point of a 3D rotation is a straight line

Scaling

$$\mathbf{S} = \begin{pmatrix} s_x & 0 & 0 & 0 \\ 0 & s_y & 0 & 0 \\ 0 & 0 & s_z & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

Translation

$$\mathbf{T} = \begin{pmatrix} 1 & 0 & 0 & v_x \\ 0 & 1 & 0 & v_y \\ 0 & 0 & 1 & v_z \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

Inverse Transformations

Suppose we apply a transformation **M** to a point **p**:

$$\mathbf{p}' = \mathbf{M}\mathbf{p}$$

What is the transformation needed to bring **p'** back to **p**?

$$\mathbf{p} =?\ \mathbf{p}'$$

We need the inverse of **M** to bring **p'** back to **p**:

$$\mathbf{M}^{-1}\mathbf{p}' = (\mathbf{M}^{-1}\mathbf{M})\mathbf{p} = \mathbf{I}\,\mathbf{p} = \mathbf{p}$$

Inverse of M

Identity transformation

$$\begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{pmatrix}$$

A 3x3 identity matrix

Inverse Transformations

$$\mathbf{T} = \begin{pmatrix} 1 & 0 & 0 & v_x \\ 0 & 1 & 0 & v_y \\ 0 & 0 & 1 & v_z \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

inverse of **T**?

$$\mathbf{T}^{-1} = \begin{pmatrix} 1 & 0 & 0 & -v_x \\ 0 & 1 & 0 & -v_y \\ 0 & 0 & 1 & -v_z \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$$\mathbf{S} = \begin{pmatrix} s_x & 0 & 0 & 0 \\ 0 & s_y & 0 & 0 \\ 0 & 0 & s_z & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

inverse of **S**?

$$\mathbf{S}^{-1} = \begin{pmatrix} \frac{1}{s_x} & 0 & 0 & 0 \\ 0 & \frac{1}{s_y} & 0 & 0 \\ 0 & 0 & \frac{1}{s_z} & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

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

inverse of $\mathbf{R}_z$?

$$\mathbf{R}_z^{-1} = \begin{pmatrix} \cos\theta & \sin\theta & 0 & 0 \\ -\sin\theta & \cos\theta & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$$= \mathbf{R}_z^T$$

Inverse of a rotation equals its transpose

Inverse of Transformation

Suppose we have a transformation **M** given by a composition of transformations:

$$\mathbf{M} = \mathbf{R} \cdot \mathbf{S} \cdot \mathbf{T}$$

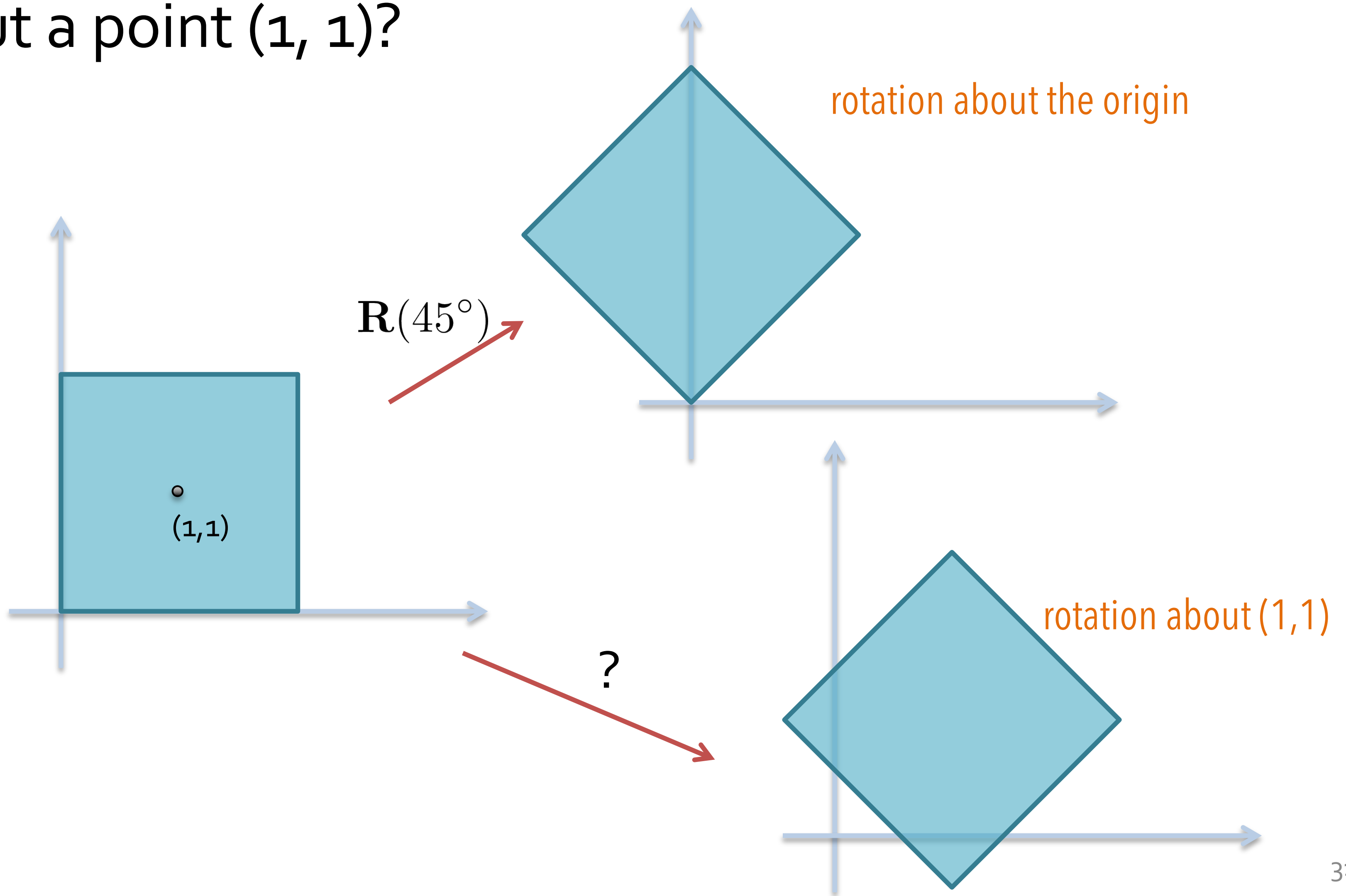
- How to find the inverse of M?

$$\begin{aligned}\mathbf{M}^{-1} &= (\mathbf{R} \cdot \mathbf{S} \cdot \mathbf{T})^{-1} \\ &= \mathbf{T}^{-1} \cdot \mathbf{S}^{-1} \cdot \mathbf{R}^{-1}\end{aligned}$$

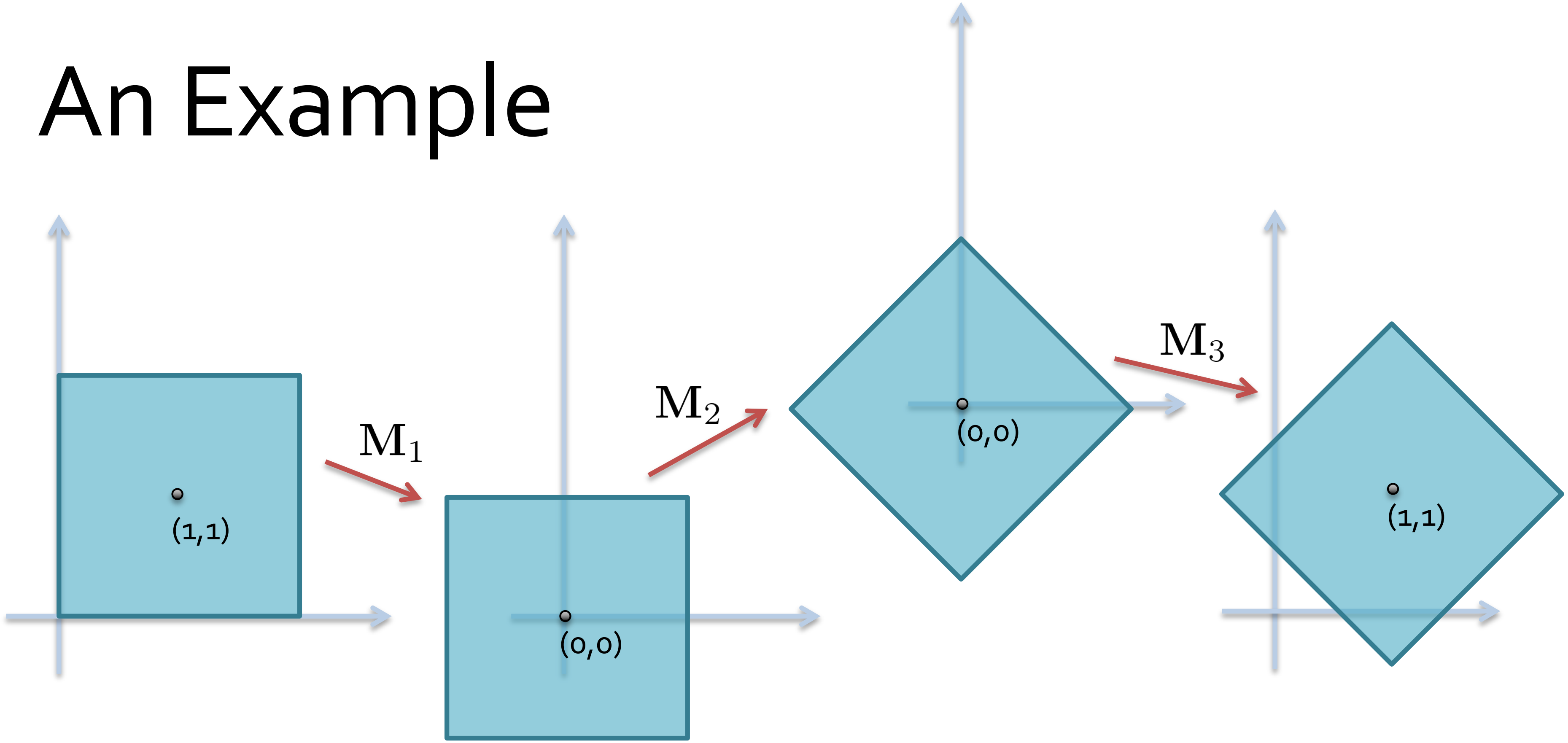
$$\begin{aligned}\mathbf{M}^{-1} \cdot \mathbf{M} &= (\mathbf{T}^{-1} \cdot \mathbf{S}^{-1} \cdot \mathbf{R}^{-1}) \cdot (\mathbf{R} \cdot \mathbf{S} \cdot \mathbf{T}) \\ &= \mathbf{T}^{-1} \cdot \mathbf{S}^{-1} \cdot (\mathbf{R}^{-1} \cdot \mathbf{R}) \cdot \mathbf{S} \cdot \mathbf{T} \\ &= \mathbf{T}^{-1} \cdot \mathbf{S}^{-1} \cdot \mathbf{I} \cdot \mathbf{S} \cdot \mathbf{T} \\ &= \cdots = \mathbf{I}\end{aligned}$$

An Example

What is the matrix representing a 2D rotation of 45° about a point (1, 1)?



An Example



translate by (1,1)　　Rotate 45º　　translate by (-1,-1)

$$\mathbf{M} = \mathbf{M}_3 \cdot \mathbf{M}_2 \cdot \mathbf{M}_1$$
$$= \mathbf{T}(1,1) \cdot \mathbf{R}(45^\circ) \cdot \mathbf{T}(-1,-1)$$

An Example

$$\mathbf{M} = \mathbf{T}(1,1)\cdot\mathbf{R}(45^\circ)\cdot\mathbf{T}(-1,-1)$$

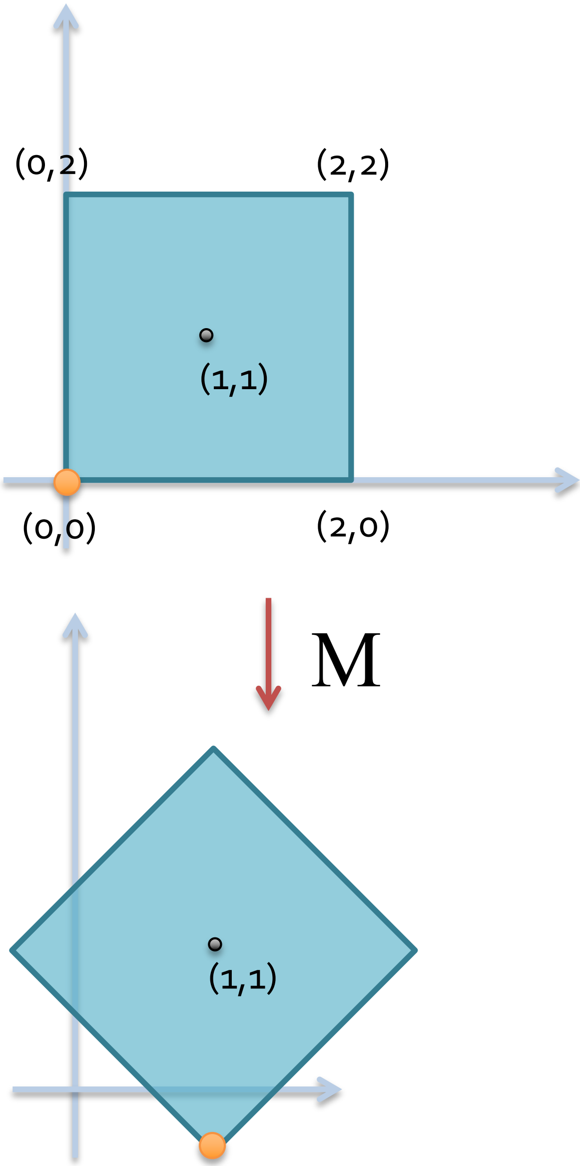
$$= \begin{pmatrix}1 & 0 & 1\\ 0 & 1 & 1\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}\cos 45^\circ & -\sin 45^\circ & 0\\ \sin 45^\circ & \cos 45^\circ & 0\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}1 & 0 & -1\\ 0 & 1 & -1\\ 0 & 0 & 1\end{pmatrix}$$

$$= \begin{pmatrix}1 & 0 & 1\\ 0 & 1 & 1\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}\cos 45^\circ & -\sin 45^\circ & -\cos 45^\circ + \sin 45^\circ\\ \sin 45^\circ & \cos 45^\circ & -\sin 45^\circ - \cos 45^\circ\\ 0 & 0 & 1\end{pmatrix}$$

$$= \begin{pmatrix}\cos 45^\circ & -\sin 45^\circ & -\cos 45^\circ + \sin 45^\circ + 1\\ \sin 45^\circ & \cos 45^\circ & -\sin 45^\circ - \cos 45^\circ + 1\\ 0 & 0 & 1\end{pmatrix}$$

$$= \begin{pmatrix}\frac{1}{\sqrt{2}} & -\frac{1}{\sqrt{2}} & 1\\ \frac{1}{\sqrt{2}} & \frac{1}{\sqrt{2}} & 1-\sqrt{2}\\ 0 & 0 & 1\end{pmatrix}$$

Where will the four vertices of the square be transformed to?



Let's try the point $p = (0,0)^T$

$$p' = \mathbf{M}p$$

$$= \begin{pmatrix} \frac{1}{\sqrt{2}} & -\frac{1}{\sqrt{2}} & 1 \\ \frac{1}{\sqrt{2}} & \frac{1}{\sqrt{2}} & 1-\sqrt{2} \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} 0 \\ 0 \\ 1 \end{pmatrix}$$

$$= \begin{pmatrix} 1 \\ 1-\sqrt{2} \\ 1 \end{pmatrix}$$