CS6533/CS4533 Lecture 4 Slides/Notes

Viewing and Projection
(Ch 5, 10, 11, 12.1, Notes)

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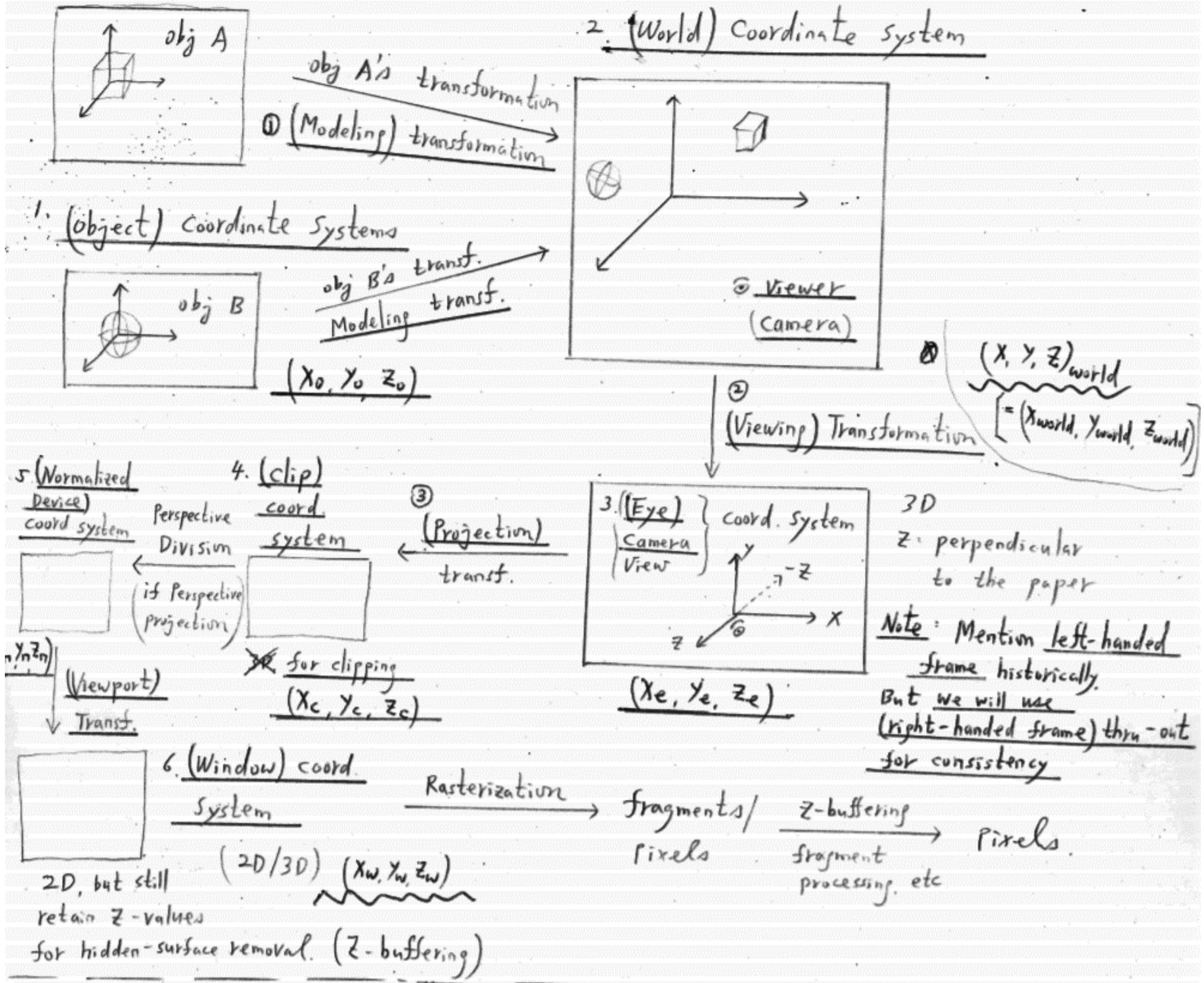
Viewing & Projection

* Coordinate Systems & Transformations



cf. World coord : $(X, Y, Z)_{world}$ $\left[=(X_{world}, Y_{world}, Z_{world})\right]$

Window : (X_w, Y_w, Z_w)

Note :

1. Modeling Transf : Rotation, Translation, Scaling
   Viewing : Coord. system change. (Using Translation & Rotation)
   } Same types ⇒ Combined into (model-view matrix)
2. Projection : Different type ⇒ Use a separate (Projection matrix)

Viewing & Projection Process : 2 Parts

1. Describe the position & orientation of Camera.

(Viewing) use model-view matrix to transform objects, world frame → {(eye) / (camera)} frame.

2. Decide type of Projection : { parallel / perspective } ⇒ (projection) matrix

(Projection) what part to image. clipping / view volume

* Concatenate $\underbrace{\text{projection matrix}}_{P}$ with $\underbrace{\text{model-view Matrix}}_{M}$

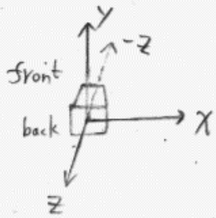
vertex → $\boxed{\text{model-view}}$ → $\boxed{\text{projection}}$

$q = (PM)p$

Viewing (Part 1): Specifying the camera position & Orientation

then transform World frame $\longrightarrow$ Camera / Eye frame

Here: camera frame is a (right-handed) frame, with the camera / eye at the origin looking at the $(-z)$ direction.



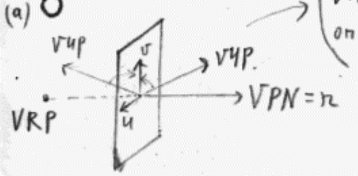
① Specify VRP — view reference point
i.e. camera / eye position

VPN — View Plane normal
i.e. normal vector to the [view / projection] plane
vector of line of sight

VUP — view up vector (camera top direction)
for

in the world frame

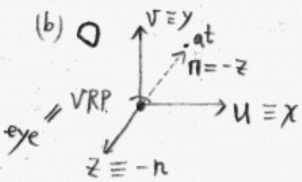
(a) O



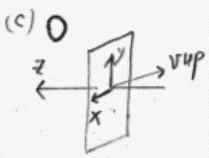
(VUP is not necessarily on the view plane)

② Construct the camera frame:
* Project VUP onto the projection plane to get v
* $n \times v = u$ to get u
* VRP as origin

(b) O



(c) O



③ Transform world frame $\longrightarrow$ camera frame

* Typically, use function LookAt(eye, at, vup) (eye, at, vup in (world frame)) to obtain a 4×4 matrix M to transform world frame $\longrightarrow$ camera frame (right-handed)

eye $\cdot \longrightarrow \cdot$ at
line of sight
$\simeq$ VPN $= n = -z$

Derivation of matrix M for LookAt( ):

(1)

$\underline{z} = -n = \text{normalize}(eye - at) = (z_1, z_2, z_3)$ (from fig (b))

$\underline{x} = u = \text{normalize}(VUP \times z) = (x_1, x_2, x_3)$ ($\because$ fig (c))

$\underline{y} = v = \text{normalize}(z \times x) = (y_1, y_2, y_3)$ ($\because$ fig (c))

origin $= eye = (eye_1, eye_2, eye_3)$

* We need to (normalize) since we need $x \cdot x = y \cdot y = z \cdot z = 1$

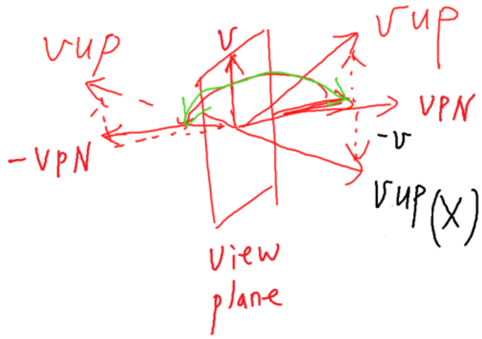
(2)

① $\text{Translate}(-eye) = \begin{bmatrix} 1 & 0 & 0 & -eye_1 \\ 0 & 1 & 0 & -eye_2 \\ 0 & 0 & 1 & -eye_3 \\ 0 & 0 & 0 & 1 \end{bmatrix}$

② Rotate:

$$\begin{bmatrix} [x] & 0 \\ [y] & 0 \\ [z] & 0 \\ 0\ 0\ 0 & 1 \end{bmatrix} = \begin{bmatrix} x_1 & x_2 & x_3 & 0 \\ y_1 & y_2 & y_3 & 0 \\ z_1 & z_2 & z_3 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = R$$

$M = R \cdot \text{Translate}(-eye)$ ※



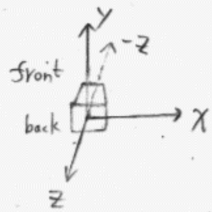
* <u>Note</u>: vup can be anywhere in the direction range vup $\leftarrow\bullet\rightarrow$ vup since in this range vup projecting onto the view plane results in the +v direction, which indicates the <u>top</u> of the camera

Any direction below -VPN $\leftarrow\bullet\rightarrow$ VPN eg. $\searrow$ vup, is wrong, since its projection onto the view plane is in the -v direction.

Viewing (Part 1): Specifying the camera position & Orientation.

then transform World frame → Camera/Eye frame

Here: camera frame is a (right-handed) frame, with the camera/eye at the origin looking at the (−z) direction.



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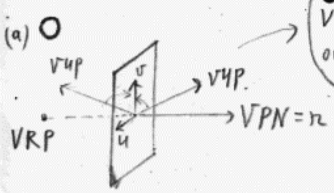
ie camera/eye position

VPN — View Plane normal
ie normal vector to the (view / projection) plane
vector of line of sight

Vup — view up vector (camera top direction) for
in the world frame

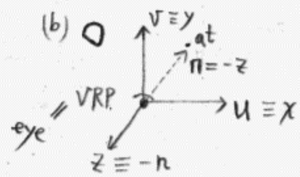
(a)



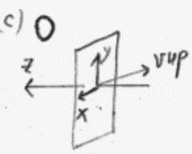
(Vup is not necessarily on the view plane)

② Construct the camera frame:
* Project Vup onto the projection plane to get v
* $n \times v = u$ to get u
* VRP as origin

(b)



(c)



③ Transform world frame → camera frame

* Typically: use function LookAt(eye, at, vup) (eye, at, vup in (world frame)) to obtain a 4×4 matrix M to transform world frame → camera frame (right-handed)

eye • → • at
line of sight = VPN = n = −z

Derivation of matrix M for LookAt( ):

(1)

$\underline{z} = -n = \text{normalize}(eye - at) = (z_1, z_2, z_3)$ (from fig (b))

$\underline{x} = u = \text{normalize}(vup \times z) = (x_1, x_2, x_3)$ (: fig (c))

$\underline{y} = v = \text{normalize}(z \times x) = (y_1, y_2, y_3)$ (: fig (c))

origin = eye = (eye_1, eye_2, eye_3)

* We need to (normalize) since we need $x \cdot x = y \cdot y = z \cdot z = 1$

(2)

① Translate(−eye) = $\begin{bmatrix} 1 & 0 & 0 & -eye_1 \\ 0 & 1 & 0 & -eye_2 \\ 0 & 0 & 1 & -eye_3 \\ 0 & 0 & 0 & 1 \end{bmatrix}$

② Rotate:

$$\begin{bmatrix} [x] & 0 \\ [y] & 0 \\ [z] & 0 \\ 0\ 0\ 0 & 1 \end{bmatrix} = \begin{bmatrix} x_1 & x_2 & x_3 & 0 \\ y_1 & y_2 & y_3 & 0 \\ z_1 & z_2 & z_3 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = R$$

M = R · Translate(−eye) ※

Verification for M [eye]$_{world}$ = (origin)$_{eye}$?

$$M = R \cdot \text{Translate}(-eye) = R \cdot \begin{bmatrix} 1 & 0 & 0 & -eye_1 \\ 0 & 1 & 0 & -eye_2 \\ 0 & 0 & 1 & -eye_3 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$M \cdot (eye)_{world}$

$$= M \cdot \begin{bmatrix} eye_1 \\ eye_2 \\ eye_3 \\ 1 \end{bmatrix} = R \cdot \begin{bmatrix} 1 & 0 & 0 & -eye_1 \\ 0 & 1 & 0 & -eye_2 \\ 0 & 0 & 1 & -eye_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \cdot \begin{bmatrix} eye_1 \\ eye_2 \\ eye_3 \\ 1 \end{bmatrix} = R \cdot \begin{bmatrix} \cancel{eye_1} + 0 + 0 + \cancel{(-eye_1) \cdot 1} \\ 0 + \underline{eye_2} + 0 - \underline{eye_2} \\ 0 + 0 + \underline{eye_3} - \underline{eye_3} \\ 0 + 0 + 0 + 1 \end{bmatrix}$$

$$= R \cdot \underbrace{\begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix}}_{\text{origin}} = \underbrace{\begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix}}_{\text{origin}} = (\text{origin})_{eye}. \checkmark$$

* origin is the fixed pt of rotation.

So R·(origin) does NOT change the origin.

Verification:

① $M \cdot \begin{bmatrix} eye \end{bmatrix}_{world} = (origin)_{eye}$?

$$M \cdot \begin{bmatrix} eye_1 \\ eye_2 \\ eye_3 \\ 1 \end{bmatrix} = R \cdot \begin{bmatrix} eye_1 + 0 + 0 - eye_1 \\ 0 + eye_2 + 0 - eye_2 \\ 0 + 0 + eye_3 - eye_3 \\ 1 \end{bmatrix} = R \cdot \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} = origin \ \checkmark$$

② $M \cdot \begin{bmatrix} x \end{bmatrix}_{world} = (e_1)_{eye}$?

$$M \cdot \begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ 0 \end{bmatrix} = \begin{bmatrix} [\ x\ ] & 0 \\ [\ y\ ] & 0 \\ [\ z\ ] & 0 \\ 0\ 0\ 0 & 1 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ 0 \end{bmatrix}$$

(∵ Translate$(-eye)$ has no effect on vector x)

$$= \begin{bmatrix} x \cdot x + 0 \\ y \cdot x + 0 \\ z \cdot x + 0 \\ 0 \end{bmatrix} = \begin{bmatrix} 1 \\ 0 \\ 0 \\ 0 \end{bmatrix} = e_1 \ \checkmark$$

Similarly.

$$M \cdot \begin{bmatrix} y_1 \\ y_2 \\ y_3 \\ 0 \end{bmatrix}_{world} = \begin{bmatrix} x \cdot y + 0 \\ y \cdot y + 0 \\ z \cdot y + 0 \\ 0 \end{bmatrix} = \begin{bmatrix} 0 \\ 1 \\ 0 \\ 0 \end{bmatrix} = (e_2)_{eye} \ \checkmark \qquad M \cdot \begin{bmatrix} z_1 \\ z_2 \\ z_3 \\ 0 \end{bmatrix}_{world} = \begin{bmatrix} x \cdot z + 0 \\ y \cdot z + 0 \\ z \cdot z + 0 \\ 0 \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 1 \\ 0 \end{bmatrix} = (e_3)_{eye} \ \checkmark$$

Note*: $M = (M^{-1})^{-1}$

$$M^{-1} = [R \cdot \text{Translate}(-eye)]^{-1} = (\text{Translate}(-eye))^{-1} \cdot R^{-1} = \text{Translate}(eye) \cdot R^{t} = \text{Translate}(eye) \begin{bmatrix} [x] & [y] & [z] & 0 \\ & & & 0 \\ & & & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$= \begin{bmatrix} 1 & 0 & 0 & eye_1 \\ 0 & 1 & 0 & eye_2 \\ 0 & 0 & 1 & eye_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x_1 & y_1 & z_1 & 0 \\ x_2 & y_2 & z_2 & 0 \\ x_3 & y_3 & z_3 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} x_1 & y_1 & z_1 & eye_1 \\ x_2 & y_2 & z_2 & eye_2 \\ x_3 & y_3 & z_3 & eye_3 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} [x] & [y] & [z] & [eye] \\ 0 & 0 & 0 & 1 \end{bmatrix} = A$$

$M = A^{-1}$ (This is the method of Textbook Sec 5.2.3 Lookat
Note that the matrix given there is just A But final M is $M = A^{-1}$)

*
Verification

① $M^{-1} (origin)_{eye} = M^{-1} \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} = \begin{bmatrix} eye_1 \\ eye_2 \\ eye_3 \\ 1 \end{bmatrix} = (eye)_{world} \ \checkmark$

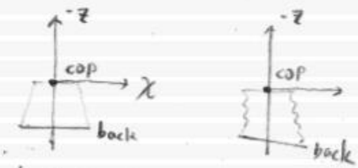
② $M^{-1} \cdot (e_1)_{eye} = M^{-1} \begin{bmatrix} 1 \\ 0 \\ 0 \\ 0 \end{bmatrix} = \begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ 0 \end{bmatrix} = (\text{vector } x)_{world} \ \checkmark$

③ $M^{-1} \cdot (e_2)_{eye} = M^{-1} \begin{bmatrix} 0 \\ 1 \\ 0 \\ 0 \end{bmatrix} = \begin{bmatrix} y_1 \\ y_2 \\ y_3 \\ 0 \end{bmatrix} = (\text{vector } y)_{world} \ \checkmark$

④ $M^{-1} \cdot (e_3)_{eye} = M^{-1} \begin{bmatrix} 0 \\ 0 \\ 1 \\ 0 \end{bmatrix} = \begin{bmatrix} z_1 \\ z_2 \\ z_3 \\ 0 \end{bmatrix} = (\text{vector } z)_{world} \ \checkmark$

Projection (Part 2)

- perspective
- parallel



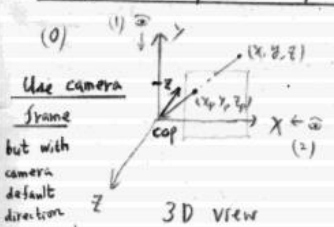
back of camera $\perp$ z axis

general case. (oblique)

Overview of Plan:
(1) Derive resulting pt q of orig. pt p by def. of projection
(2) Derive projection matrix M: $q = Mp$

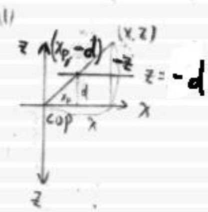
Simple perspective projection (back $\perp$ z axis)

(0) Use camera frame but with camera default direction (facing $-z$)



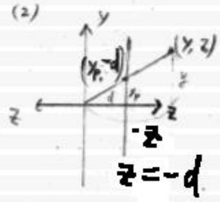
3D view

(1)



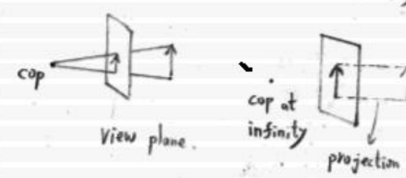
top view

(2)



side view

Def: perspective / parallel/orthogonal



projection lines are $\parallel$ to each other
All are $\perp$ to the view plane

$z_p = -d,\ z < 0$ $(d > 0)$

$$\frac{x}{-z} = \frac{x_p}{d} \quad \Rightarrow x_p = \frac{x \cdot d}{-z}$$

$$\frac{y}{-z} = \frac{y_p}{d} \quad \Rightarrow y_p = \frac{y \cdot d}{-z}$$

$$(x_p, y_p, z_p) = \left(\frac{x \cdot d}{-z}, \frac{y \cdot d}{-z}, -d\right)$$

$$\begin{bmatrix} \frac{x \cdot d}{-z} \\ \frac{y \cdot d}{-z} \\ -d \\ 1 \end{bmatrix} \xleftarrow{\text{perspective division}} \begin{bmatrix} xd \\ yd \\ zd \\ -z \end{bmatrix} = \underbrace{\begin{bmatrix} d & 0 & 0 & 0 \\ 0 & d & 0 & 0 \\ 0 & 0 & d & 0 \\ 0 & 0 & -1 & 0 \end{bmatrix}}_{M} \underbrace{\begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}}_{p}$$

q' ≡ q

$$p = \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix} \qquad M = \begin{bmatrix} d & 0 & 0 & 0 \\ 0 & d & 0 & 0 \\ 0 & 0 & d & 0 \\ 0 & 0 & -1 & 0 \end{bmatrix} \quad \Rightarrow q = Mp = \begin{bmatrix} xd \\ yd \\ zd \\ -z \end{bmatrix}$$

projection matrix for simple perspective projection

$$q' = \begin{bmatrix} \frac{xd}{-z} \\ \frac{yd}{-z} \\ -d \\ 1 \end{bmatrix} = \cancel{\begin{bmatrix} x_p \\ y_p \\ -d \\ 1 \end{bmatrix}} = \begin{bmatrix} x_p \\ y_p \\ z_p \\ 1 \end{bmatrix}$$

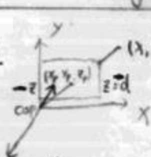
perspective division.

Remark: Homogeneous coord. system: If $w \neq 0$, $\begin{bmatrix} x \\ y \\ z \\ w \end{bmatrix} \equiv \begin{bmatrix} x/w \\ y/w \\ z/w \\ 1 \end{bmatrix}$ equivalent representation but different ~~compl~~ computation cost $\rightarrow$: perspective division.

vertices $\longrightarrow$ Model-View $\longrightarrow$ Projection $\longrightarrow$ Perspective division $\longrightarrow$

Simple Orthogonal Projection (back $\perp$ z axis)

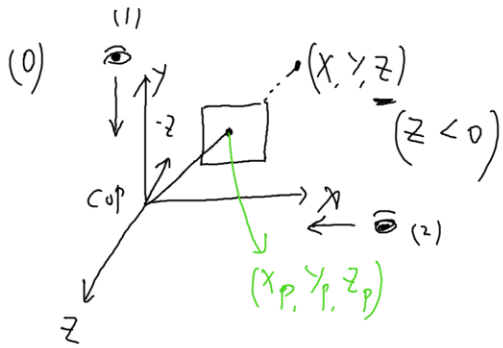
Use camera frame but with ~~theme~~ camera default dir (facing $-z$)



$(d \geq 0$, $z < 0)$

$$\begin{cases} x_p = x \\ y_p = y \\ z_p = -d \end{cases} \quad \begin{bmatrix} x \\ y \\ -d \\ 1 \end{bmatrix} = \underbrace{\begin{bmatrix} x_p \\ y_p \\ z_p \\ 1 \end{bmatrix}}_{q} = \underbrace{\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & -d \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{M} \underbrace{\begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}}_{p}$$

(value of d does not matter as long as $d \geq 0$)

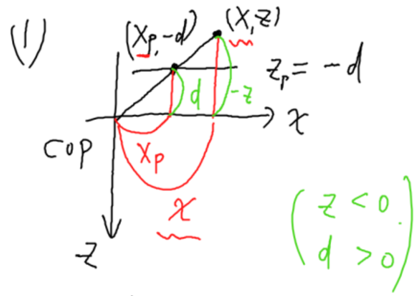


3D View

View plane: $z_p = -d \quad (d > 0)$

$z < 0$.

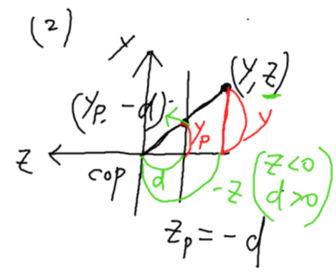
$$q \parallel (x_p, y_p, z_p) = \left(\frac{x \cdot d}{-z},\ \frac{y \cdot d}{-z},\ -d \right)$$



Top View

$$\frac{x_p}{x} = \frac{d}{-z}$$

$$\Rightarrow x_p = \frac{x \cdot d}{-z}$$



Side View

$$\frac{y_p}{y} = \frac{d}{-z}$$

$$\Rightarrow y_p = \frac{y \cdot d}{-z}$$

Now Express Perspective Projection by Matrix Multiplication:

$$q = \begin{bmatrix} \frac{x \cdot d}{-z} \\ \frac{y \cdot d}{-z} \\ -d \\ 1 \end{bmatrix} = \overset{M}{\begin{bmatrix} A & B & C & D \\ & & & \\ & & & \\ & & & \end{bmatrix}} \overset{p}{\begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}}$$

$$\frac{x \cdot d}{-z} = Ax + By + Cz + D$$

We want: A, B, C, D be constants independent of x, y, z.

$\Rightarrow$ NOT possible!!

Key Idea: Use Homogeneous Coord. System.

If $w \neq 0$: $\begin{bmatrix} x \\ y \\ z \\ w \end{bmatrix} \overset{\text{Perspective Division}}{\equiv} \begin{bmatrix} x/w \\ y/w \\ z/w \\ 1 \end{bmatrix}$

$w \neq 1$: pt. with coord. $(x/w, y/w, z/w)$

$$\underbrace{\begin{bmatrix} \frac{x \cdot d}{(-z)} \\ \frac{y \cdot d}{(-z)} \\ -d \\ 1 \end{bmatrix}}_{q} \equiv \begin{bmatrix} \frac{x \cdot d}{(-z)} \cdot (-z) \\ \frac{y \cdot d}{(-z)} \cdot (-z) \\ -d \cdot (-z) \\ 1 \cdot (-z) \end{bmatrix} = \underbrace{\begin{bmatrix} x \cdot d \\ y \cdot d \\ z \cdot d \\ -z \end{bmatrix}}_{\text{Perspective Division}} = \underbrace{\begin{bmatrix} d & 0 & 0 & 0 \\ 0 & d & 0 & 0 \\ 0 & 0 & d & 0 \\ 0 & 0 & -1 & 0 \end{bmatrix}}_{M \text{ Desired Matrix}} \underbrace{\begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}}_{p}$$

* For any point p:

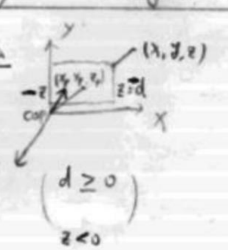
① $M \cdot p$

② Perform Perspective Division to get the projection point q.

Next, we look at Orthogonal Projection:

Simple Orthogonal Projection (back ⊥ z axis).

Use camera frame but with camera default dir (facing $-z$)



$$\begin{cases} x_p = x \\ y_p = y \\ z_p = -d \end{cases} \qquad \begin{bmatrix} x \\ y \\ -d \\ 1 \end{bmatrix} = \underbrace{\begin{bmatrix} x_p \\ y_p \\ z_p \\ 1 \end{bmatrix}}_{q} = \underbrace{\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & -d \\ 0 & 0 & 0 & 1 \end{bmatrix}}_{M} \underbrace{\begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}}_{p}$$

(value of d does not matter as long as $d \geq 0$)

Note: There is no division involved.

(Therefore, we call the division in the perspective projection perspective division.)

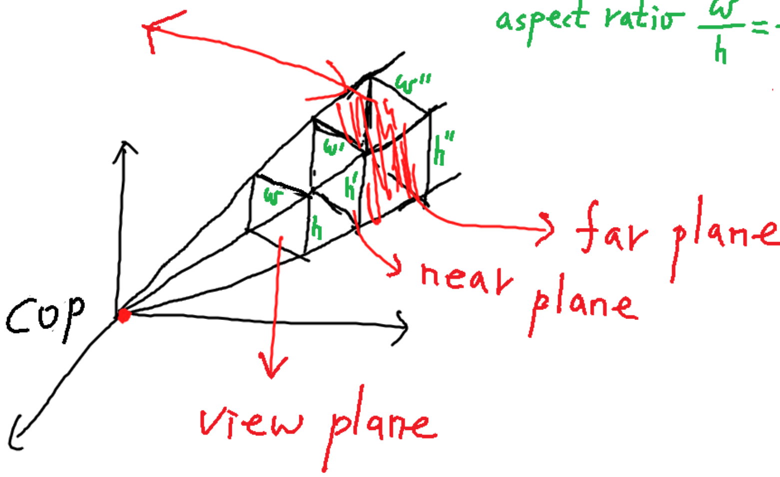
In Perspective Projection:

View $\begin{cases} \text{Volume} \\ \text{Frustum} \end{cases}$

clipping op:

$\ast$ objects outside the view volume are clipped out.

aspect ratio $\frac{w}{h} = \frac{w'}{h'} = \frac{w''}{h''}$



Perspective (;)

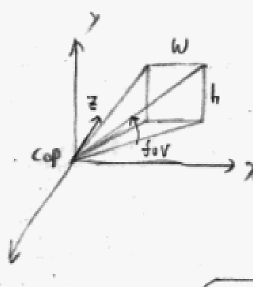
camera frame

② gluPerspective(fovy, aspect, near, far)

Easier to use than glFrustum( )

field of view degree $\in [0°, 180°)$

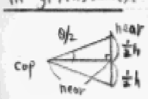
again must be > 0 (view from cop)



$\text{aspect} = \frac{w}{h}$

Note: cop is in the center of graphics window & view volume is symmetric

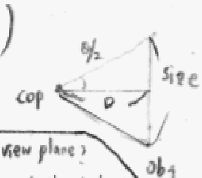
• Recover the same info as in glFrustum():



$\tan\frac{\theta}{2} = \frac{\frac{h}{2}}{\text{near}} \Rightarrow h$

$\text{aspect} = \frac{w}{h} \Rightarrow w$

field of view: (side view)



$\tan\frac{\theta}{2} = \frac{\text{size}/2}{D}$

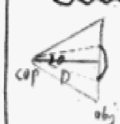
$\theta = \text{fovy}$.

⊙ Q: Where is the view plane?

A: In theory, we need the distance from cop to the view plane ie $z_p = d > 0$ on P.3 (In the projection matrix M d is used in M)
But in OpenGL, d is implemented as a default value and we don't/can't change it (actually no need to change it)

→ In OpenGL, view plane = near clipping plane.

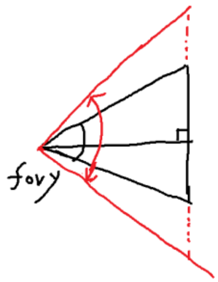
⊙ After specifying obj and cop in the world, D is fixed (Also, window is fixed)



$\Rightarrow \theta \uparrow$ more objects are in the scene, objects appear smaller ie zoom out.

$\theta \downarrow$: zoom in

Perspective (fovy, aspect, near, far)



When fovy increases, more objects enter the fixed-sized graphics window.

$\Rightarrow$ objects appear smaller

$\Rightarrow$ zoom out effect.

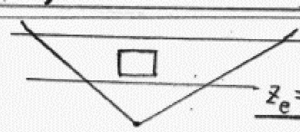
Similarly, when fovy $\Downarrow$ $\Rightarrow$ objects appear bigger

$\Rightarrow$ zoom in effect.

Perspective Normalization : Transform (distort) the entire scene so that the view volume is (axis-parallel) and the "same" perspective projection result is still kept

except that the aspect ratio of the view plane becomes (1) (It will be (restored) later in (viewport) transformation.)

$\Rightarrow$ (clipping) becomes very simple



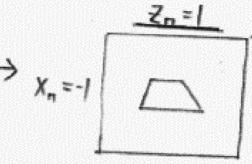
$z_e = -far$ (<0)

$z_e = -near$ (<0)

cop

near, far >0

eye coord.



$z_n = 1$

$x_n = -1$ $x_n = 1$

$z_n = -1$

(canonical view volume)

normalized device coord.

$(x_n, y_n, z_n \in [-1, 1])$