# **2D COMPUTER GRAPHICS**

Diego Nehab Summer 2019

IMPA

# **GEOMETRY AND TRANSFORMATIONS**

Points defined by pair of coordinates

- Signed distances to perpendicular directed lines
- Point where lines cross is the origin

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Basis of analytic geometry

• Connection between Euclidean geometry and algebra

Points defined by pair of coordinates

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- Connection between Euclidean geometry and algebra
- Describe shapes with equations
- E.g., lines and circles

Find intersection between line and circle?

Find intersection between line and circle?

Find intersection between two circles?

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Prove that the medians of a triangle are concurrent?

Set of V of vectors closed by linear combinations

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- Given origin *o*, associate vector v = p o to each point *p*
- Basis  $\mathcal{B} = \{v_1, v_2\}$  for V
  - Linear independent set of vectors

 $\mathcal{B}$  is l.i.  $\Leftrightarrow \alpha_1 V_1 + \alpha_2 V_2 = 0 \Rightarrow \alpha_1 = \alpha_2 = 0$ 

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That spans V

$$\mathsf{V} \in \mathsf{V} \Leftrightarrow \exists \alpha_1, \alpha_2 \mid \mathsf{V} = \alpha_1 \mathsf{V}_1 + \alpha_2 \mathsf{V}_2$$

$$[\mathbf{V}]_{\mathcal{B}} = \begin{bmatrix} \alpha_1 \\ \alpha_2 \end{bmatrix} \Leftrightarrow \mathbf{V} = \alpha_1 \mathbf{V}_1 + \alpha_2 \mathbf{V}_2$$

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Linear transformations preserve linear combinations

$$T(\alpha_1 \mathsf{v}_1 + \alpha_2 \mathsf{v}_2) = \alpha_1 T(\mathsf{v}_1) + \alpha_2 T(\mathsf{v}_2)$$

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Matrix of a linear transformation

$$[T]_{\mathcal{B}} = \begin{bmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \end{bmatrix}$$

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General linear group

Composition, inverse

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General linear group

- $\cdot$  Composition, inverse
- Preserves collinearity, parallelism, concurrency, tangency, ratios of distances along lines

Dot product, scalar product, standard inner product  $u^{T}v = u \cdot v = \langle u, v \rangle = u_{x}v_{x} + u_{y}v_{y}$  Dot product, scalar product, standard inner product  $u^T v = u \cdot v = \langle u, v \rangle = u_x v_x + u_y v_y$ 

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$$\langle u, v \rangle = \frac{1}{4} (\|u + v\|^2 - \|u - v\|^2)$$

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Let u and v make angles  $\alpha$  and  $\beta$  with the x-axis

$$\cos(\beta - \alpha) = \cos(\alpha)\cos(\beta) + \sin(\alpha)\sin(\beta)$$
$$= u_x/||u||v_x/||v|| + u_y/||u||v_y/||v||$$
$$= \langle u, v \rangle/(||u||||v||)$$

Dot product, scalar product, standard inner product

$$u^{\mathsf{T}}v = u \cdot v = \langle u, v \rangle = u_{\mathsf{x}}v_{\mathsf{x}} + u_{\mathsf{y}}v_{\mathsf{y}} = \|u\|\|v\|\cos(\angle uov)$$

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# **EUCLIDEAN GEOMETRY**

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Euclidean group

- Rigid transformations (isometries), or
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How to represent?
Few properties are exclusive to Euclidean geometry Similarity group

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How to represent?

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- Let V be a vector space with basis  $\mathcal{B} = \{v_1, v_2\}$  and o a point
- Affine space is  $A = o + V = \{p \mid p o \in V\}$

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Let V be a vector space with basis  $\mathcal{B} = \{v_1, v_2\}$  and o a point

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• Affine frame  $C = \{v_1, v_2; o\}$ 

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Affine coordinates

$$[p]_{\mathcal{C}} = \begin{bmatrix} \alpha_1 \\ \alpha_2 \\ 1 \end{bmatrix}$$

Let V be a vector space with basis  $\mathcal{B} = \{v_1, v_2\}$  and o a point Barycentric frame  $\mathcal{D} = \{a_0, a_1, a_2\} = \{o, o + v_1, o + v_2\}$ 

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$$p = 0 + \alpha_1 v_1 + \alpha_2 v_2$$
  
=  $(1 - \alpha_1 - \alpha_2)0 + \alpha_1(0 + v_1) + \alpha_2(0 + v_2)$   
=  $(1 - \alpha_1 - \alpha_2)a_0 + \alpha_1a_1 + \alpha_2a_2$   
=  $\alpha_0a_0 + \alpha_1a_1 + \alpha_2a_2$ , with  $\alpha_0 + \alpha_1 + \alpha_2 = 1$ .

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- Displacement vectors  $v \in V$  are such that  $\sum_{i=0}^{2} \alpha_i = 0$
- Points  $p \in A$  are such that  $\sum_{i=0}^{2} \alpha_i = 1$  (affine combination)

Preserve affine combinations

 $\alpha_0 + \alpha_1 + \alpha_2 = 1 \Rightarrow$  $T(\alpha_0 a_0 + \alpha_1 a_1 + \alpha_2 a_2) = \alpha_0 T(a_0) + \alpha_1 T(a_1) + \alpha_2 T(a_2)$ 

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Matrix of an affine transformation in affine frame

$$[T]_{\mathcal{C}} = \begin{bmatrix} a_{11} & a_{12} & t_1 \\ a_{21} & a_{22} & t_2 \\ 0 & 0 & 1 \end{bmatrix}$$

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• Translation, rotation, scale

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- Centered rotation

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What about the matrix in barycentric frame  $\mathcal{D} = \{a_0, a_1, a_2\}$ 

Affine group

• Non-singular linear transformation and translation

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Visualization of the affine plane

Line ax + by + c = 0

$$n^{T}p = 0$$
, with  
 $n^{T} = \begin{bmatrix} a & b & c \end{bmatrix}$  and  $p = \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$ 

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• How does it change with an affine transformation?

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Projective lines: planes through origin in 3D

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Projective plane

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Projective lines: planes through origin in 3D

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Projective plane

• Affine plane augmented with ideal points

Homogeneous coordinates

• Generalization of affine coordinates

$$\begin{bmatrix} a \\ b \\ c \end{bmatrix}, \quad a, b, c \text{ not all zero} \qquad \begin{bmatrix} w x \\ w y \\ w \end{bmatrix} \equiv \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

 $W \neq 0$ 

Combination of three arbitrary perspective transformations

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Matrix of a projective transformation

$$[T] = \begin{bmatrix} a_{11} & a_{12} & a_{13} \\ a_{21} & a_{22} & a_{23} \\ a_{31} & a_{32} & a_{33} \end{bmatrix}$$

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Must be invertible

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- $\cdot\,$  Non-singular linear transformations in  $R^3$
- Preserves collinearity, tangency, cross-ratios
- Maps between any two sets of 4 points non-collinear 3 by 3
- All lines meet, even parallel lines
- All quadrilaterals are the same
- All conics are the same

## References

D. A. Brannan, M. F. Esplen, and J. J. Gray. *Geometry*. Cambridge University Press, 2011.