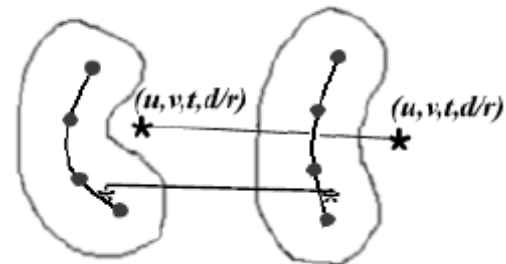
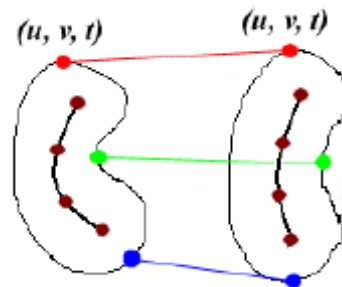


Free Form Deformation

Simulating Deformation

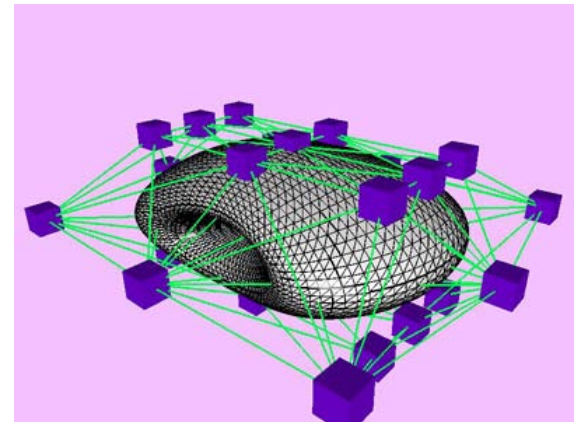
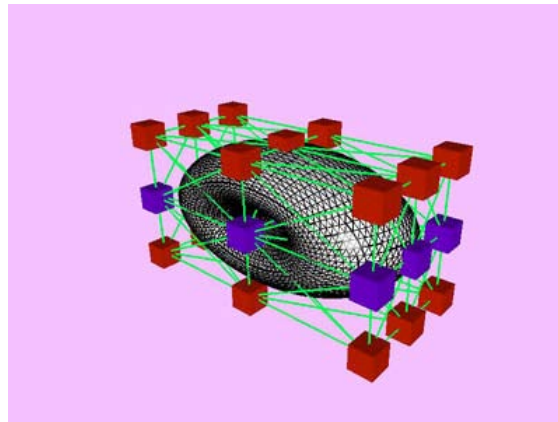
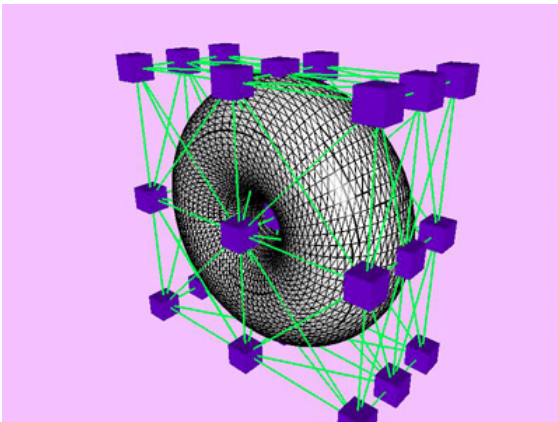
-- various approaches

- Physics-based Simulations
 - Particle system, string system...
 - Finite differences, finite element, boundary element methods...
 - ...
- ...
- **Free form deformation**
- M-reps based deformation



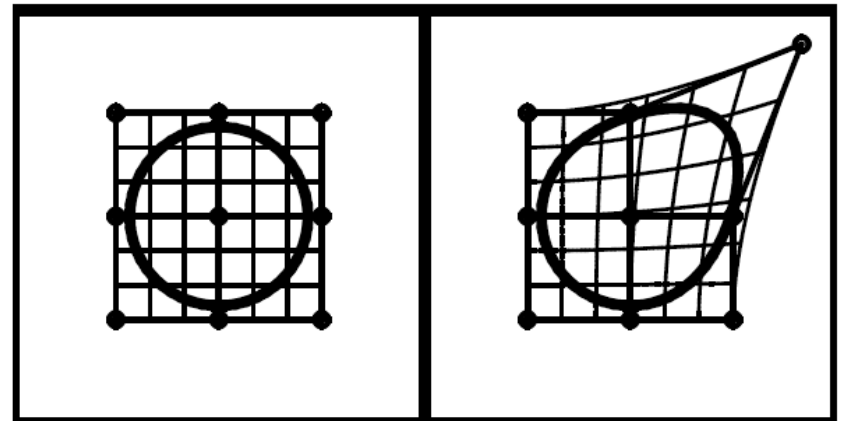
Free-form deformation (FFD)

- Embed the object into a domain that is more easily parametrized than the object.
- Advantages:
 - You can deform arbitrary objects
 - Independent of object representation



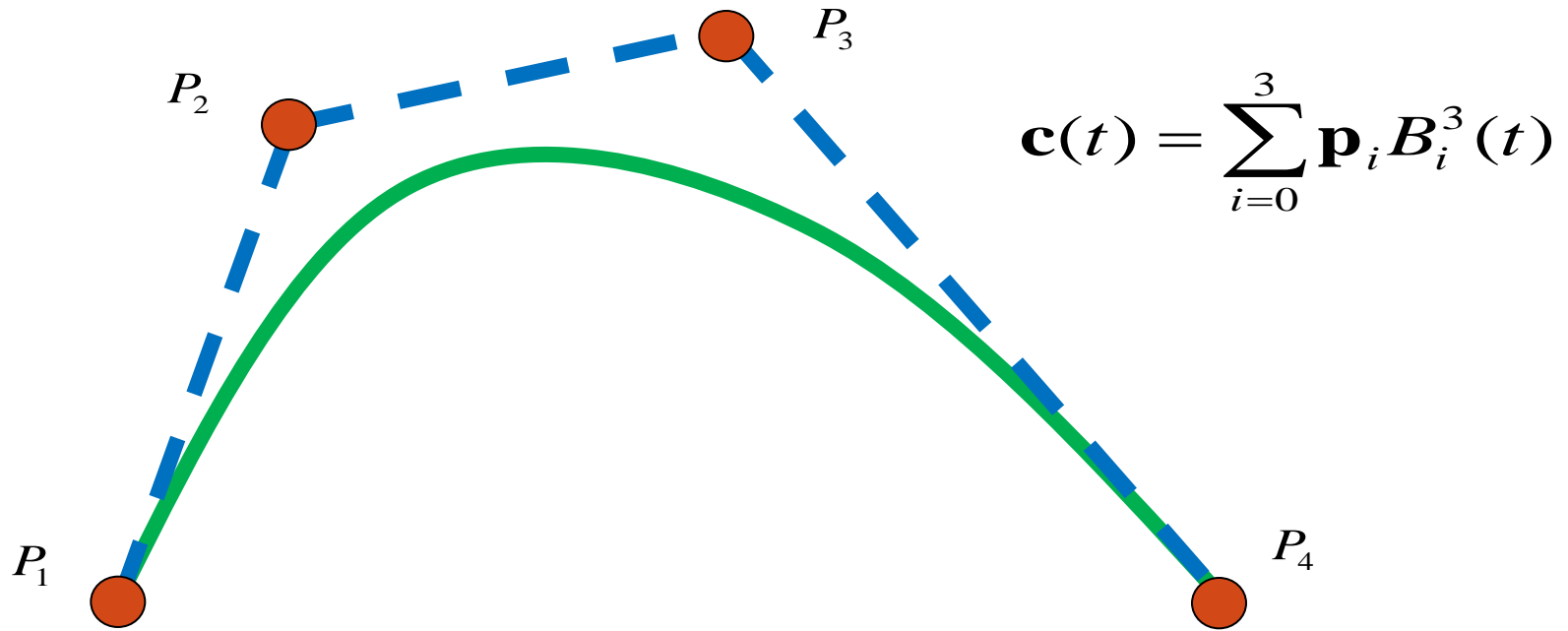
2D FFD

- 2D FFD = a map from R^2 to R^2
 - When the space deforms, defines a new position for every point in the new space
 - Any lines or curves that lie in that space are altered (see the figure)
 - The space deformation is easily manipulated by control points



Remind the "Bezier Curve"

Interpolate the two end control points,
and approximates the other two points:



$$Q'(0) = 3(P_2 - P_1); Q'(1) = 3(P_4 - P_3)$$

Review: Bernstein Polynomials

- Bezier curve

$$\mathbf{c}(t) = \sum_{i=0}^3 \mathbf{p}_i B_i^3(t)$$

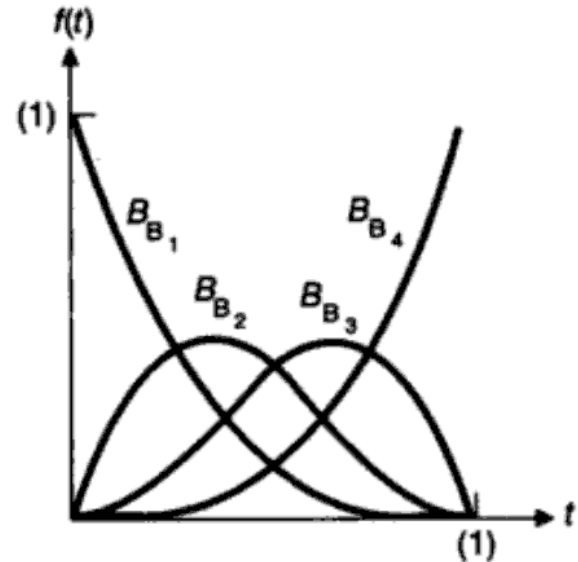
- Control points \mathbf{P} and basis functions B

$$B_0^3(t) = (1-t)^3$$


$$B_1^3(t) = 3t(1-t)^2$$

$$B_2^3(t) = 3t^2(1-t)$$

$$B_3^3(t) = t^3$$




Review: B-Splines and NURBS

B-Spline 
$$\mathbf{c}(u) = \sum_{i=0}^n \mathbf{p}_i B_{i,k}(u)$$

□ NURBS = Non Uniform Rational B-Splines

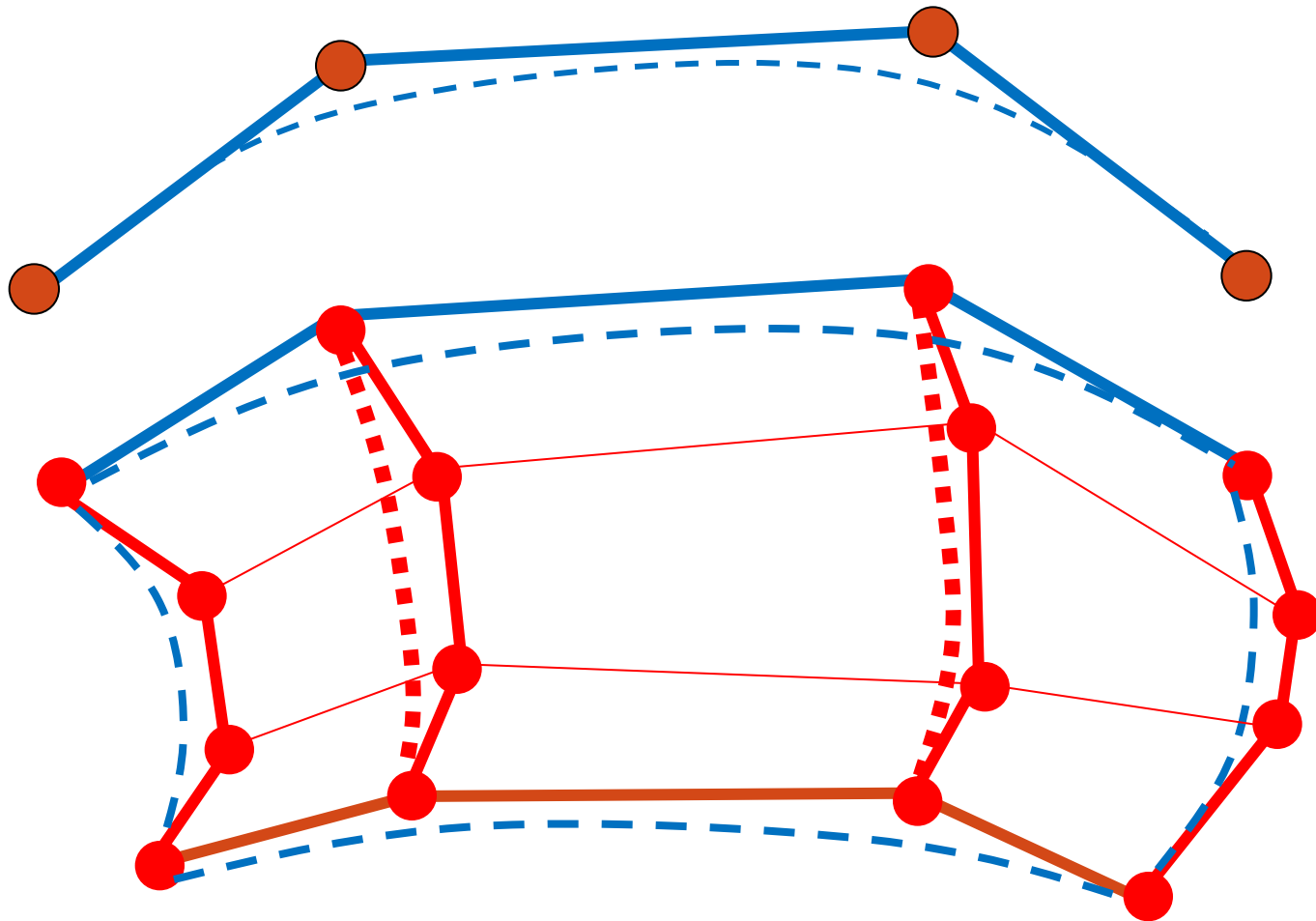
By generalizing B-splines
using Homogeneous
Coordinates

$$\mathbf{c}(u) = \sum_{i=0}^n \begin{bmatrix} \mathbf{p}_{i,x} w_i \\ \mathbf{p}_{i,y} w_i \\ \mathbf{p}_{i,z} w_i \\ w_i \end{bmatrix} B_{i,k}(u)$$

NURBS 
$$\mathbf{c}(u) = \frac{\sum_{i=0}^n \mathbf{p}_i w_i B_{i,k}(u)}{\sum_{i=0}^n w_i B_{i,k}(u)}$$

1D→2D

B-spline Curves → B-spline Surfaces



Tensor Product Surfaces

Basis functions: bivariate functions of u and v
(constructed as products of univariate basis functions)

A tensor product surface $S^T(u, v) = (x(u, v), y(u, v), z(u, v)) = \sum_{i=0}^n \sum_{j=0}^m f_i(u) g_j(v) b_{i,j};$

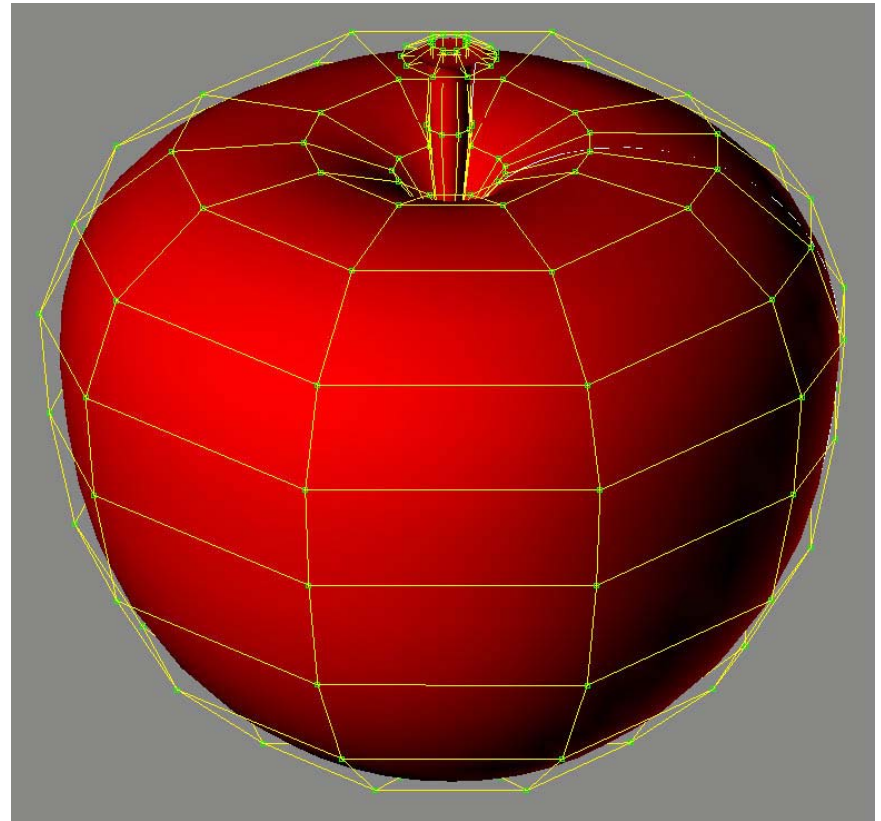
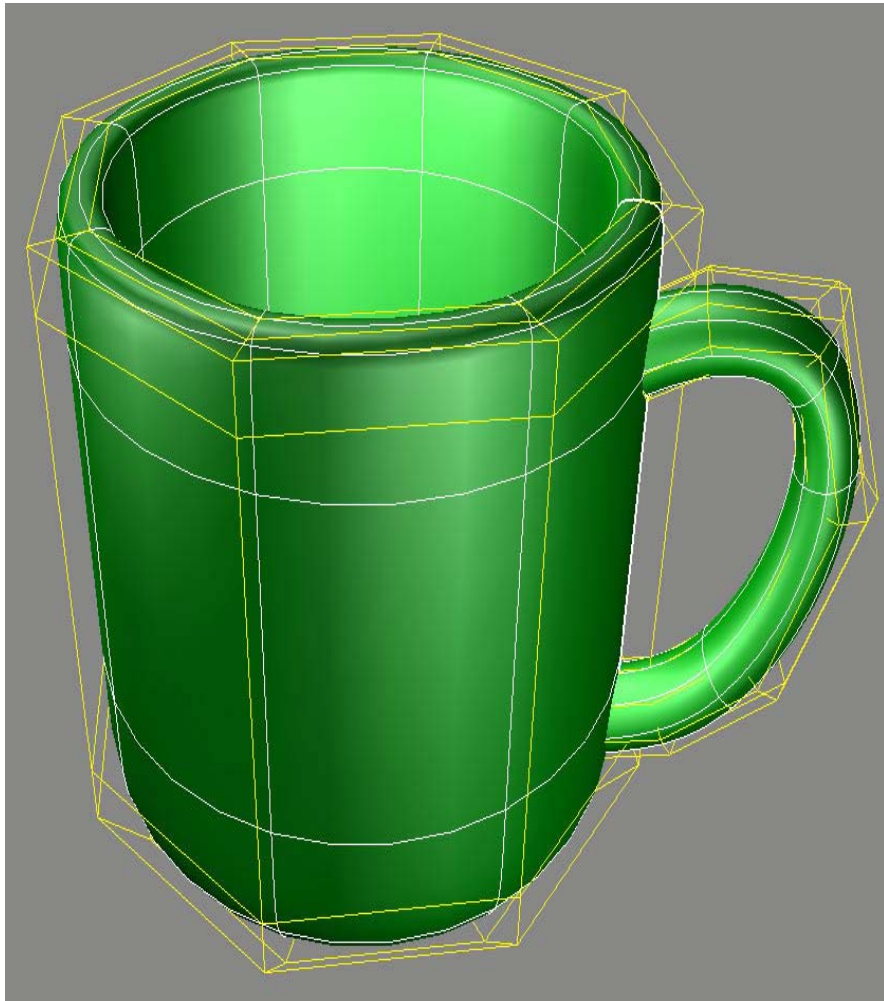
$$\text{where } \begin{cases} b_{i,j} = (x_{i,j}, y_{i,j}, z_{i,j}) \\ 0 \leq u, v \leq 1 \end{cases}$$

The (u, v) domain of this mapping is a square (rectangle)

$$S^T(u, v) = [f_i(u)]^T [b_{i,j}] [g_j(v)]$$


 $(n+1) * (m+1)$ matrix of 3D points

NURBS Surface Examples



Parametric Solids

- Tricubic solid

$$\mathbf{p}(u, v, w) = \sum_{i=0}^3 \sum_{j=0}^3 \sum_{k=0}^3 \mathbf{a}_{ijk} u^i v^j w^k$$

$$u, v, w \in [0,1]$$

- Bezier solid

$$\mathbf{p}(u, v, w) = \sum_i \sum_j \sum_k \mathbf{p}_{ijk} B_i(u) B_j(v) B_k(w)$$

- B-spline solid

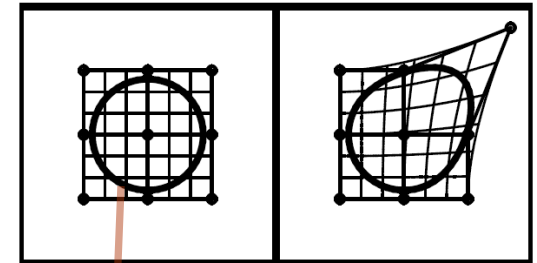
$$\mathbf{p}(u, v, w) = \sum_i \sum_j \sum_k \mathbf{p}_{ijk} B_{i,I}(u) B_{j,J}(v) B_{k,K}(w)$$

- NURBS solid

$$\mathbf{p}(u, v, w) = \frac{\sum_i \sum_j \sum_k \mathbf{p}_{ijk} q_{ijk} B_{i,I}(u) B_{j,J}(v) B_{k,K}(w)}{\sum_i \sum_j \sum_k q_{ijk} B_{i,I}(u) B_{j,J}(v) B_{k,K}(w)}$$

Formulation of 2D FFD

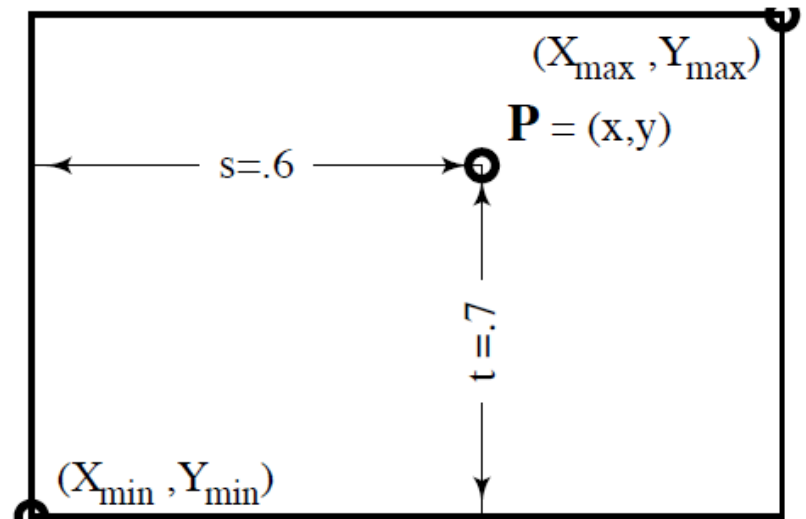
$$\mathbf{X}(s, t) = \frac{\sum_{j=0}^n \sum_{i=0}^m w_{ij} B_i^m(s) B_j^n(t) \mathbf{P}_{ij}}{\sum_{j=0}^n \sum_{i=0}^m w_{ij} B_i^m(s) B_j^n(t)}$$



where $B_i^n(t)$ and $B_j^m(s)$ are Bézier blending functions, and s and t are the local coordinates of a point with respect to the deformation region.

\mathbf{P}_{ij} are the actual (x, y) coordinates of the displaced control point i, j .

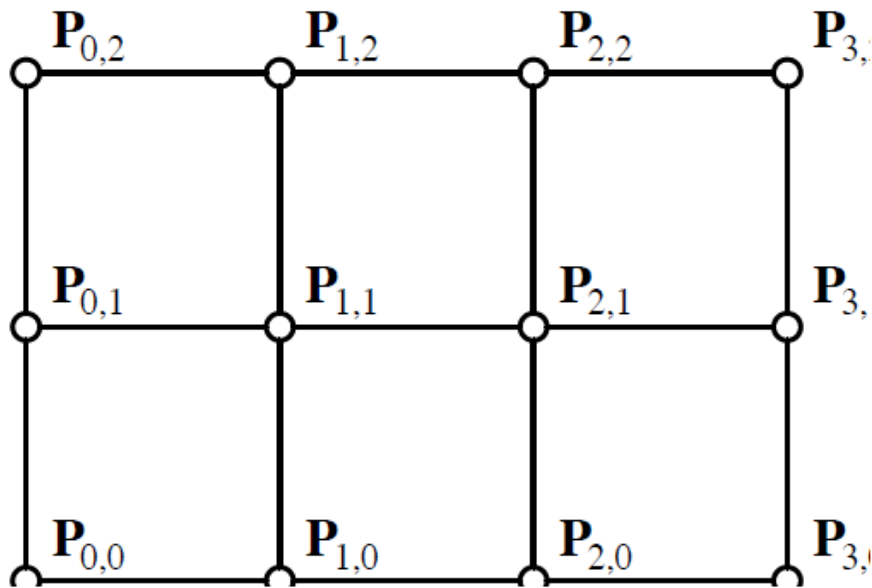
$$s = \frac{x - X_{min}}{X_{max} - X_{min}}, \quad t = \frac{y - Y_{min}}{Y_{max} - Y_{min}}$$



Formulation of 2D FFD (cont.)

In their initial, undisplaced position, the control points form a rectangular grid:

$$\mathbf{P}_{i,j} = \left(X_{min} + \frac{i}{m}(X_{max} - X_{min}), Y_{min} + \frac{j}{n}(Y_{max} - Y_{min}) \right)$$

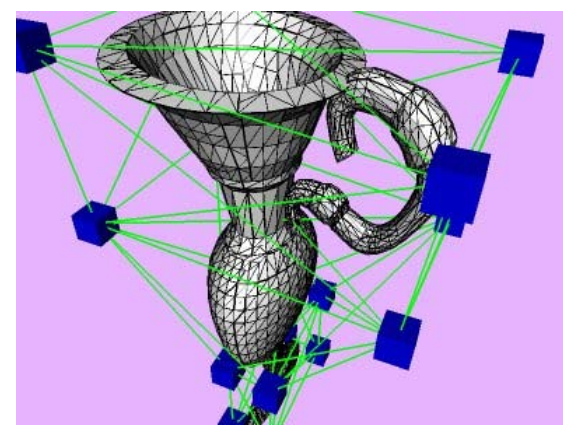
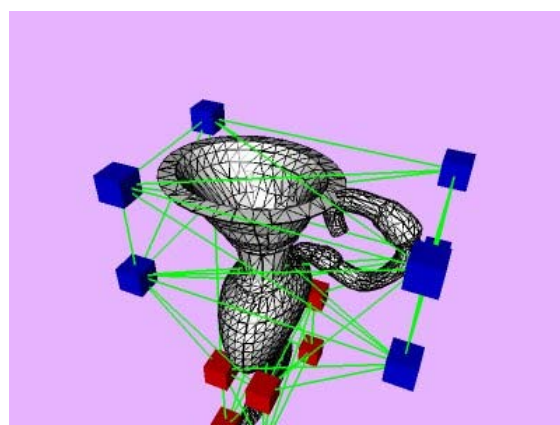
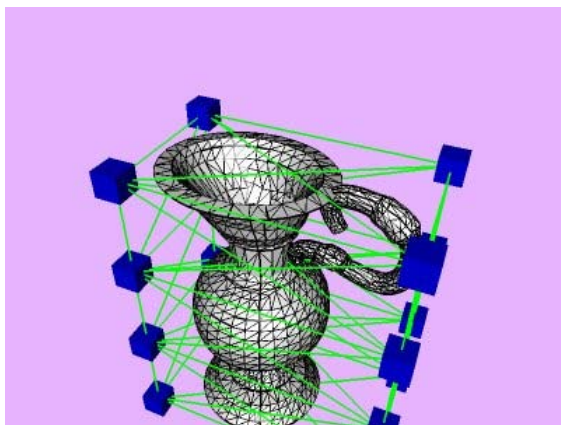
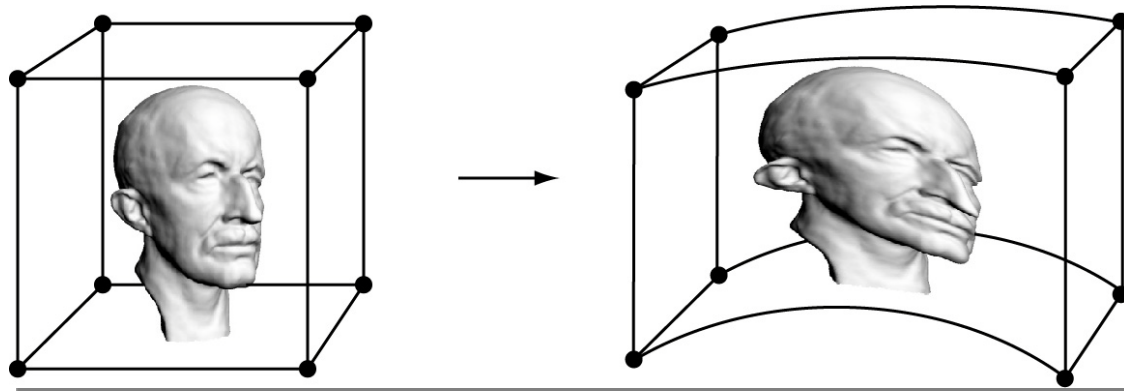


To deform the object:

1. Generate control points net
2. Compute (s,t) coordinates of every sample point Q
3. Move the control points
4. Evaluate new position of Q using

$$\mathbf{X}(s,t) = \frac{\sum_{j=0}^n \sum_{i=0}^m w_{ij} B_i^m(s) B_j^n(t) \mathbf{P}_{ij}}{\sum_{j=0}^n \sum_{i=0}^m w_{ij} B_i^m(s) B_j^n(t)}$$

Generalize to 3D easily



Another example and application

