2D Graphics
2D Raster Graphics

- Integer grid
- Sequential (left-right, top-down) scan
**Line drawing**

- A very important operation
  - used frequently, block diagrams, bar charts, engineering drawing, architecture plans, etc.
  - curves as concatenation of small line segments
- Criteria
  - line should appear straight

*illuminate nearest grid point*
Line drawing

- Line should terminate correctly
- Line should have a constant intensity

specify both end points instead of end point + slope + length

brightness adjustment (antialiasing)

intensity \sim \# \text{ of dots/unit length}
Line drawing

- Line should not have “gaps”

\[ y = f(x) \text{ if } |\text{slope}| < 1 \]
\[ x = f(y) \text{ if } |\text{slope}| > 1 \]
Line drawing

- Line should be drawn as fast as possible
  - Brute-force method
  - DDA (digital differential analyzer)

\[
y = mx + b \Rightarrow \quad 1 \text{ fp } *
\]

\[
for \ (i = x_o;i < x_n;i + +) \quad 1 \text{ fp } +
\]

\[
y_i = m \cdot i + b
\]

\[
y_{i+1} = mx_{i+1} + b
\]

\[
= m (x_i + 1) + b \quad 1 \text{ fp } +
\]

\[
= mx_i + b + m
\]

\[
= y_i + m
\]
Bresenham’s Line Algorithm

integer operations only

\[ (0,0) \rightarrow (x_2 - x_1, y_2 - y_1) \]

if \( s > t \) or \( s - t > 0 \) \( \Rightarrow \) \( \square \ t_i \)

else \( s < t \) or \( s - t < 0 \) \( \Rightarrow \) \( \blacksquare \ s_i \)
possible current intersection range

possible next intersection range

$45^\circ$

$45^\circ$
Bresenham’s Line Algorithm

\[ s_i = \frac{dy}{dx}(x_{i-1} + 1) - y_{i-1} \]

\[ t_i = (y_{i-1} + 1) - \frac{dy}{dx}(x_{i-1} + 1) \]

\[ s_i - t_i = 2\frac{dy}{dx}(x_{i-1} + 1) - 2y_{i-1} - 1 \]

\[ dx(s_i - t_i) = 2(x_{i-1}dy - y_{i-1}dx) + 2dy - dx \]

Floating point

Integer!!
Bresenham’s Line Algorithm

\[ d_i = 2(x_{i-1}dy - y_{i-1}dx) + 2dy - dx \]

\[ d_{i+1} = 2(x_idy - y_idx) + 2dy - dx \]

\[ \Rightarrow d_{i+1} - d_i = 2dy(x_i - x_{i-1}) - 2dx(y_i - y_{i-1}) \]

\[ \Rightarrow d_{i+1} - d_i = 2dy - 2dx(y_i - y_{i-1}) \]

\[ \Rightarrow d_{i+1} = d_i + 2dy - 2dx(y_i - y_{i-1}) \]
Bresenham’s Line Algorithm

\[ d_{i+1} = d_i + 2dy - 2dx(y_i - y_{i-1}) \]

*if* \( d_i \geq 0 *choose t_i \)

\[ \Rightarrow y_i = y_{i-1} + 1 \]

\[ \Rightarrow d_{i+1} = d_i + 2(dy - dx) \]

*if* \( d_i < 0 *choose s_i \)

\[ \Rightarrow y_i = y_{i-1} \]

\[ \Rightarrow d_{i+1} = d_i + 2dy \]

*initial condition* \( d_1 = 2dy - dx (x_0, y_0) = (0,0) \)

•Complexity: 1 left shift + 2 integer additions
Circle Drawing

- Symmetry reduces drawing to 1/8

\[ x = x_c + r \cos \theta \]
\[ y = y_c + r \sin \theta \]
Bresenham’s Circle Algorithm

integer operations only

\[ (x_{c}, y_{c}) = (0, 0) \]

\[ 45^\circ < \theta < 90^\circ \]

\[ D(s_i) = (x_{i-1} + 1)^2 + (y_{i-1} - 1)^2 - r^2 \]

\[ D(t_i) = (x_{i-1} + 1)^2 + y_{i-1}^2 - r^2 \]

\[ |D(s_i)| > |D(t_i)| \quad \Rightarrow \quad t_i \]

\[ |D(s_i)| < |D(t_i)| \quad \Rightarrow \quad s_i \]
Bresenham’s Circle Algorithm

\[ d_i = |D(s_i)| - |D(t_i)| = -D(s_i) + D(t_i) \]

\[ d_i = 2r^2 - 2(x_{i-1} + 1)^2 - (y_{i-1} - 1)^2 - y_{i-1}^2 \]

\[ d_{i+1} = 2r^2 - 2(x_{i-1} + 2)^2 - (y_i - 1)^2 - y_i^2 \]

\[ \Rightarrow d_{i+1} - d_i = -4x_{i-1} - 6 - 2(y_i^2 - y_{i-1}^2) - 2(y_i - y_{i-1}) \]
Bresenham’s Circle Algorithm

\[ d_1 = -3 + 2r \quad (x_0, y_0) = (0, r) \]

if \( d_i \geq 0 \) choose \( t_i \)

\[ \Rightarrow y_i = y_{i-1}, d_{i+1} = d_i - 4x_{i-1} - 6 \]

if \( d_i < 0 \) choose \( s_i \)

\[ \Rightarrow y_i = y_{i-1} - 1, d_{i+1} = d_i - 4x_i + 4y_i - 6 \]

• Complexity: only integer and shift operations
Other primitives

- Ellipse
  - symmetry reduces to 1/4
  - Bresenhem’s ellipse algorithm

- Curve
  - difficult
  - approximation using short line segments
  - general curve forms (Bezier, B-spline, etc.)

- Characters
  - rectangular grid patterns
Polygon Filing

- Arbitrary # of sides
- Convex or concave
- Holes
Scan Line Algorithm

- Edge table
  - sort edges by scanline (using min Y)
  - record
    - x coordinate of ymin
    - ymax
    - $\Delta x$ to be added

\[ (x, y_{\text{min}}) \]

\[ y_{\text{max}} \]

\[ y_{i+1} \]

\[ y_i \]

\[ \Delta x \]
Scan Line Algorithm

- Set y to smallest y in ET
- Initialize AET to be Null
- Repeat until AET and ET are empty
  - move from ET bucket y to AET those edges whose ymin=y
  - sort edges in AET by x (insertion sort)
  - fill in pixel values in between x pairs
  - remove from AET those edges whose ymax = y
  - increment y by 1
  - update x for all edges in AET \( x \leftarrow x + \Delta x \)
Polygon Patterned Filling
Polygon Patterned Filling

- Pattern can be anchored at
  - a fixed point: transparent object moves on a patterned background
  - a polygon corner: patterned object
2D Transformation

- For animation, manipulation, user interaction
- Translation, rotation, scaling

\[
\begin{bmatrix}
x' \\
y'
\end{bmatrix} = \begin{bmatrix} x \\ y \end{bmatrix} + \begin{bmatrix} T_x \\ T_y \end{bmatrix}
\]

\[
\begin{bmatrix}
x' \\
y'
\end{bmatrix} = \begin{bmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}
\]

\[
\begin{bmatrix}
x' \\
y'
\end{bmatrix} = \begin{bmatrix} S_x & 0 \\ 0 & S_y \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}
\]
A Very Common Confusion

- What is being transformed? Points or coordinate system?
- For CG, pipeline operations are always applied to features (points, lines, curves, planes)
- But you can think in either way:
  - Points are physically moved in a fixed coordinate system (e.g., in modeling transform), or
  - A coordinate system is moved, while points stay stationary (e.g., in viewing transform)
  - Both interpretations are useful
2D Rigid Transformations

- A rigid transformation maps one coordinate system into another
  - Preserves distances and angles
- To transform points from one coordinate frame to another, find the rigid transformation that brings the two coordinate frames in alignment
  - **Translate** so that their origins coincide
  - **Rotate** so that their axes coincide (x with x, y with y, and z with z)
2D examples

Trans

Rot

Trans+Rot
2D Translation

- Translate the coordinate system by \((Tx, Ty)\)
- What is the translated point?

\[ P' = P + \begin{bmatrix} -T_x \\ -T_y \end{bmatrix} \]
2D rotation matrix

- Rotate $\theta$ counterclockwise
- What is the transformation $R$?

$P' = RP$

$P' = \begin{bmatrix} \cos \theta & \sin \theta \\ -\sin \theta & \cos \theta \end{bmatrix} P$
A rigid transformation moves an object from one location to another location.

Preserves distances and angles.

To transform points from one place to another, find the rigid transformation that

- Translate so that the object moves
- Rotate so that the object reorients
2D examples

Trans

Rot

Trans+Rot
2D Translation

- Translate the coordinate system by (Tx, Ty)

- What is the translated point?

\[ P' = P + \begin{bmatrix} T_x \\ T_y \end{bmatrix} \]

Diagram:
- Origin
- Point P
- Translated point P'
- Translation vectors (-Tx, -Ty) and (Tx, Ty)
2D rotation matrix

- Rotate \( \theta \) counterclockwise
- What is the transformation \( R \)?

\[
P' = RP
\]

\[
P' = \begin{bmatrix}
\cos \theta & -\sin \theta \\
\sin \theta & \cos \theta
\end{bmatrix} P
\]
2D Transformation

- For animation, manipulation, user interaction
- translation, rotation, scaling

\[
\begin{bmatrix}
  x' \\
  y'
\end{bmatrix} = \begin{bmatrix}
  x \\
  y
\end{bmatrix} + \begin{bmatrix}
  T_x \\
  T_y
\end{bmatrix}
\]

\[
\begin{bmatrix}
  x' \\
  y'
\end{bmatrix} = \begin{bmatrix}
  \cos \theta & -\sin \theta \\
  \sin \theta & \cos \theta
\end{bmatrix} \begin{bmatrix}
  x \\
  y
\end{bmatrix}
\]

\[
\begin{bmatrix}
  x' \\
  y'
\end{bmatrix} = \begin{bmatrix}
  S_x & 0 \\
  0 & S_y
\end{bmatrix} \begin{bmatrix}
  x \\
  y
\end{bmatrix}
\]
2D Transformation (cont.)

- Inconsistent representation for translation
- Cannot be concatenated
- Troublesome for
  - Hierarchical transforms
  - Interactive, incremental display

\[ P = R_n \cdots (R_3 (R_2 (R_1 P + T_1) + T_2) + T_3) \cdots + T_n \]
Homogeneous Coordinates

- consistent representation for all three
- can be concatenated & pre-computed

\[(x, y) \rightarrow (wx, wy, w), w \neq 0\]
\[(wx, wy, w) \rightarrow (wx/w, wy/w)\]
\[
\begin{bmatrix}
    x' \\
    y' \\
    1
\end{bmatrix} = \begin{bmatrix}
    1 & 0 & T_x \\
    0 & 1 & T_y \\
    0 & 0 & 1
\end{bmatrix}\begin{bmatrix}
    x \\
    y \\
    1
\end{bmatrix}
\]

\[
\begin{bmatrix}
    x' \\
    y' \\
    1
\end{bmatrix} = \begin{bmatrix}
    \cos \theta & -\sin \theta & 0 \\
    \sin \theta & \cos \theta & 0 \\
    0 & 0 & 1
\end{bmatrix}\begin{bmatrix}
    x \\
    y \\
    1
\end{bmatrix}
\]

\[
\begin{bmatrix}
    x' \\
    y' \\
    1
\end{bmatrix} = \begin{bmatrix}
    S_x & 0 & 0 \\
    0 & S_y & 0 \\
    0 & 0 & 1
\end{bmatrix}\begin{bmatrix}
    x \\
    y \\
    1
\end{bmatrix}
\]

\[
\begin{bmatrix}
    x' \\
    y' \\
    1
\end{bmatrix} = (TRS)\begin{bmatrix}
    x \\
    y \\
    1
\end{bmatrix}
\]
How about other transforms?

- For example, reflection

Mirrored images of each other
Try to represent the new transform as a composite of T, R, S

\[ \begin{bmatrix} \cos \theta & -\sin \theta & 0 \\ \sin \theta & \cos \theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & -1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \cos \theta & -\sin \theta & 0 \\ \sin \theta & \cos \theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \]

\[ \theta = -\tan^{-1}\left(\frac{b}{a}\right) \]

\[ \theta = \tan^{-1}\left(\frac{b}{a}\right) \]
Clipping Against Upright Rectangular Window

- Points

\[ \text{if } x_{\text{min}} \leq x \leq x_{\text{max}} \text{ and } y_{\text{min}} \leq y \leq y_{\text{max}} \]

\[ \text{then accept otherwise reject} \]
Clipping Against Upright Rectangular Window

- **Lines**
  - trivially accepted if both end points inside
  - otherwise **Points**

\[
x_1 + t(x_2 - x_1) = x'_1 + t'(x'_2 - x'_1)
\]

\[
y_1 + t(y_2 - y_1) = y'_1 + t'(y'_2 - y'_1)
\]

\[0 \leq t, t' \leq 1\]

\[(x_1, y_1), (x_2, y_2) : \text{end points of line}\]

\[(x'_1, y'_1), (x'_2, y'_2) : \text{end points of window boundary}\]
Cohen-Sutherland Line-Clipping Algorithm

- Outcodes
  - bit1 --above: ymax-y
  - bit2 --below: y-ymin
  - bit3 --right of: xmax-x
  - bit4 --left of: x-xmin
- Trivially-accept: both end points having outcode 0000
- Trivially-reject: corresponding bits in two outcodes are set, or outcode1 & outcode2 nonzero
Neither: need more testing

E.g. mid-point algorithm

- divide a line segment \((x_1, y_1), (x_2, y_2)\) into two line segments
  \((x_1, y_1), ((x_1 + x_2) / 2, (y_1 + y_2) / 2)\)
  \(((x_1 + x_2) / 2, (y_1 + y_2) / 2), (x_2, y_2)\)
- test each line independently
- recursive division if necessary
- guarantee to stop in \(O(\log n)\) steps
Cyrus-Beck (Liang-Basky) Line Clipping

- Can be more efficient when intersection tests are unavoidable
- Work in the parameter \((t)\) space to locate true intersections before calculating 2D coordinates
- Work for all kinds of clipping polygons and in 3D
- Two basic steps:
  - find intersections \((t)\)
  - classify intersections
Cyrus-Beck (Liang-Basky) Line Clipping

- Find intersections

\[
\begin{align*}
N \cdot (P(t) - P_E) &= 0 \\
N \cdot (P_o + t(P_1 - P_o) - P_E) &= 0 \\
tN \cdot (P_1 - P_o) + N \cdot (P_o - P_E) &= 0 \\
t &= \frac{N \cdot (P_o - P_E)}{-N \cdot (P_1 - P_o)}
\end{align*}
\]

- \( N = (a, b) \)
- \( ax + by + c = 0 \)
- Intersections outside \((0,1)\) range are not valid
- But intersection inside \((0,1)\) range might not be valid either
Cyrus-Beck (Liang-Basky) Line Clipping

- Classify intersections

\[ N \cdot (P_1 - P_o) < 0 \] PE (potentially entering)

\[ N \cdot (P_1 - P_o) > 0 \] PL (potentially leaving)
- Locate the largest PE point & $t > 0$
- Locate the smallest PL point & $t < 1$
- PE < PL for a valid line
Polygon Clipping (Sutherland-Hodgman)

- Given an ordered sequence of polygon vertices
- And a convex clipping polygon
- Output ordered clipped polygon vertices
- Using divide-and-conquer, one clipping edge at a time
Original Right boundary clipping
Bottom boundary clipping

Left boundary clipping
Top boundary clipping
Other Primitives

- Use of extents (extents for a whole string, words, individual characters)
- Divide and Conquer