Hierarchical Modeling and Scene Graphs

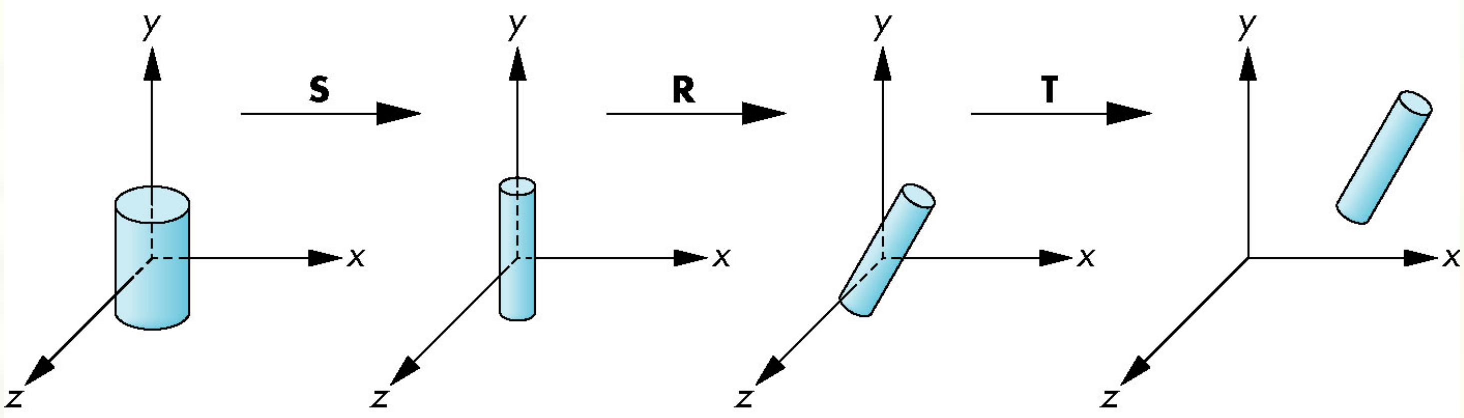
Adapted from material prepared by Ed Angel

Objectives

- Examine the limitations of linear modeling
    - Symbols and instances
- Introduce hierarchical models
    - Articulated models
    - Robots
- Introduce Tree and DAG models
- Examine various traversal strategies
- Generalize the notion of objects to include lights, cameras, attributes
- Introduce scene graphs

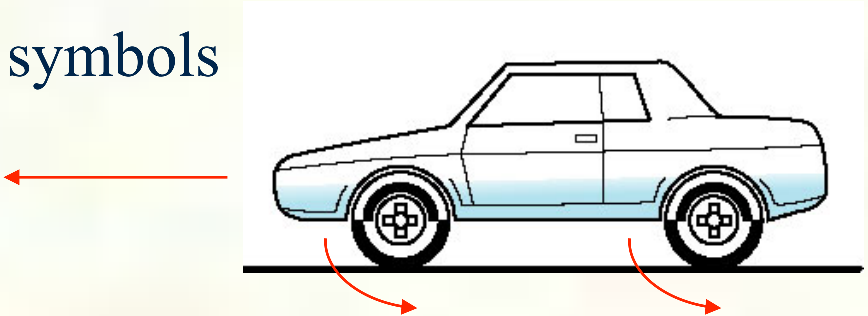
Instance Transformation

- Start with a prototype object (a *symbol*)
- Each appearance of the object in the model is an *instance*
  - Must scale, orient, position
  - Defines instance transformation



Relationships in Car Model

- Symbol-instance table does not show relationships between parts of model
- Consider model of car
  - Chassis + 4 identical wheels
  - Two symbols



- Rate of forward motion determined by rotational speed of wheels

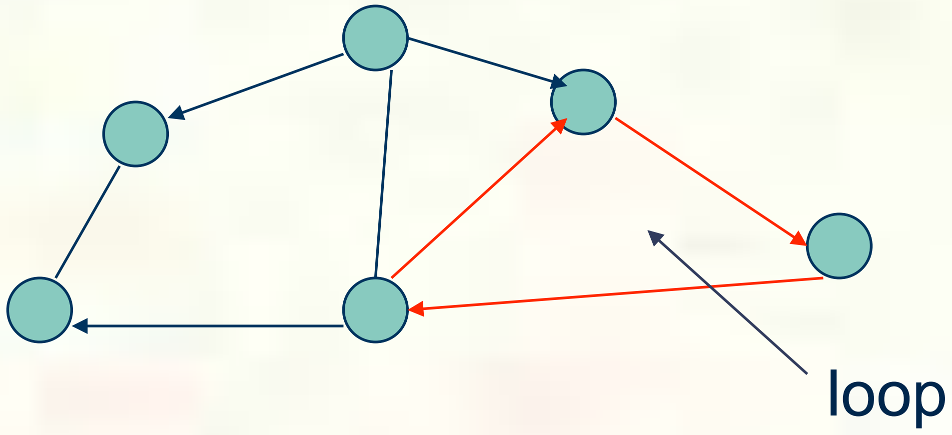
Structure Through Function Calls

```
car(speed){
    chassis()
    wheel(right_front);
    wheel(left_front);
    wheel(right_rear);
    wheel(left_rear);
}
```

- Fails to show relationships well
- Look at problem using a graph

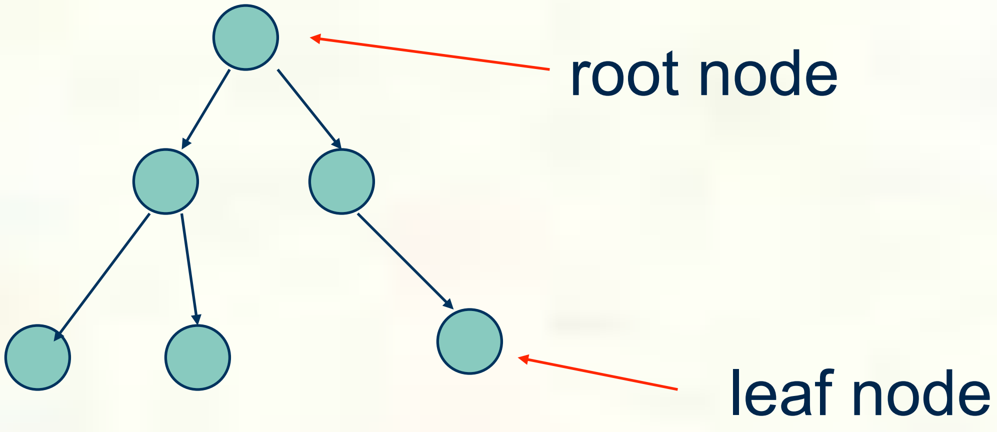
Graphs

- Set of *nodes* and *edges (links)*
- Edge connects a pair of nodes
  - Directed or undirected
- *Cycle*: directed path that is a loop

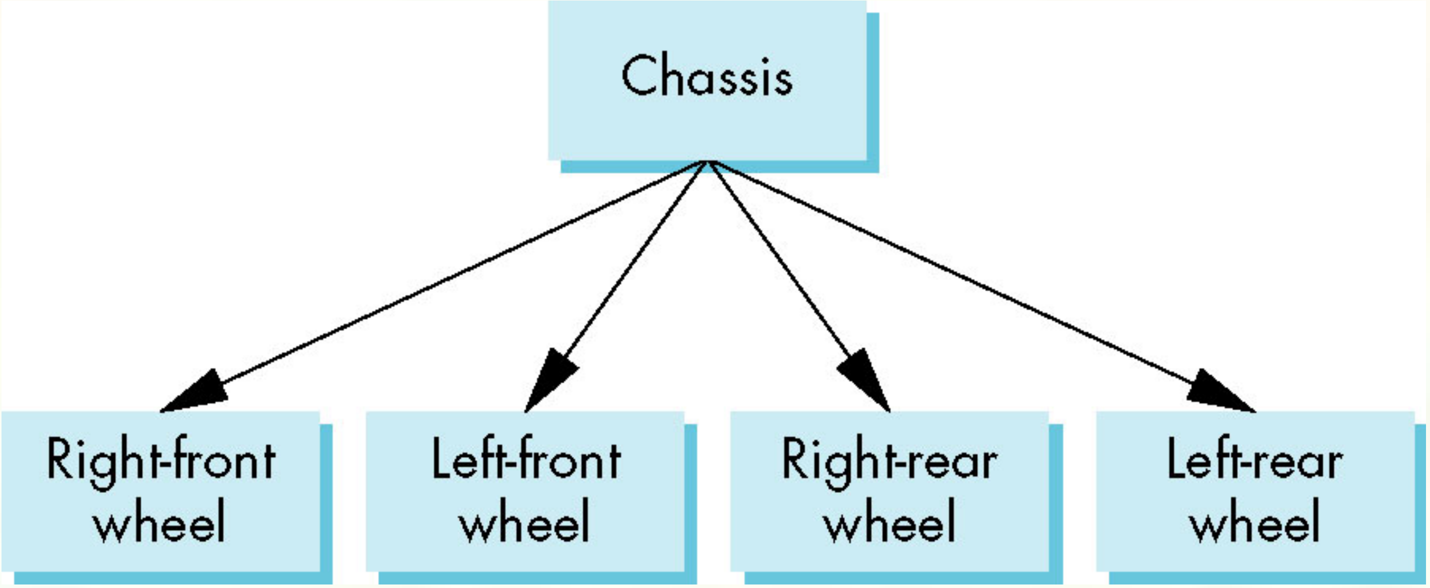


Tree

- Graph in which each node (except the root) has exactly one parent node
  - May have multiple children
  - Leaf or terminal node: no children



Tree Model of Car



Chassis

Right-front wheel

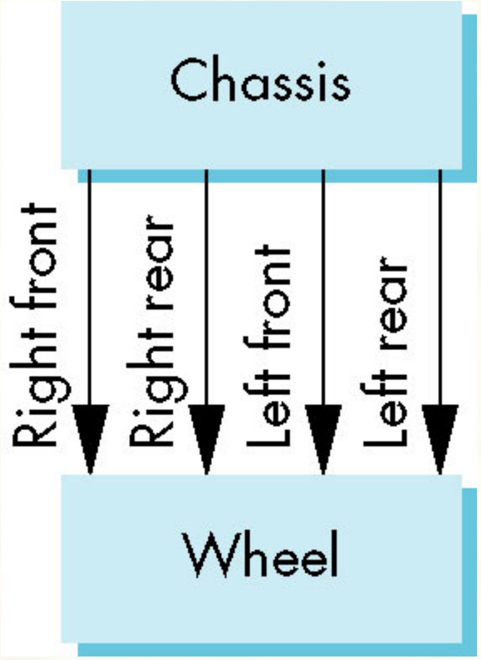
Left-front wheel

Right-rear wheel

Left-rear wheel

DAG Model

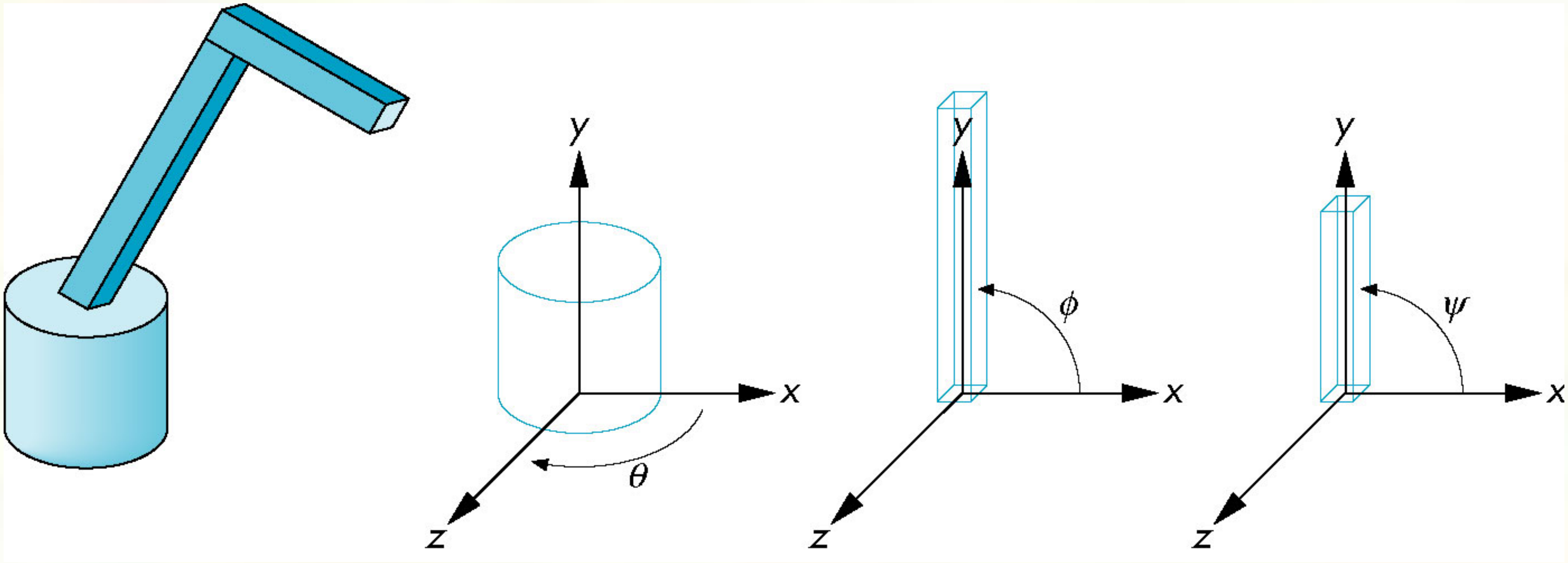
- If we use the fact that all the wheels are identical, we get a *directed acyclic graph*
  - Not much different than dealing with a tree



Modeling with Trees

- Must decide what information to place in nodes and what to put in edges
- Nodes
  - What to draw
  - Pointers to children
- Edges
  - May have information on incremental changes to transformation matrices (can also store in nodes)

Robot Arm

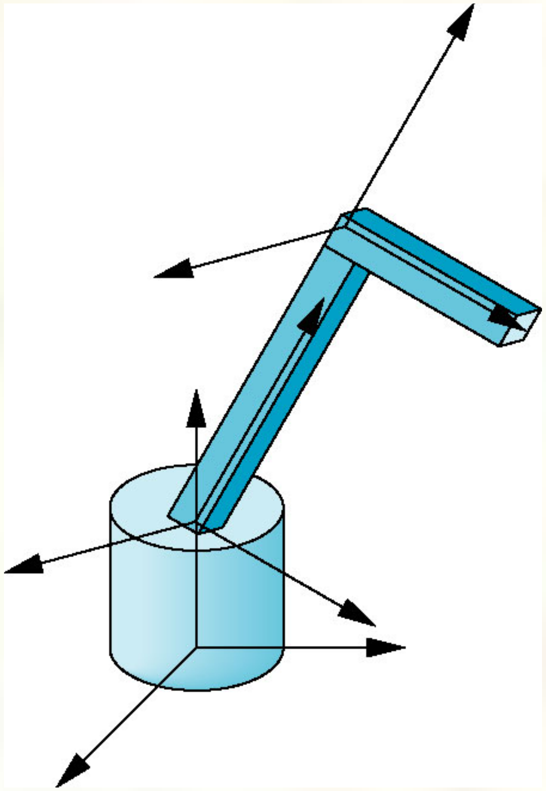


robot arm

parts in their own coodinate systems

Articulated Models

- Robot arm is an example of an *articulated model*
  - Parts connected at joints
  - Can specify state of model by giving all joint angles



Relationships in Robot Arm

- Base rotates independently
  - Single angle determines position
- Lower arm attached to base
  - Its position depends on rotation of base
  - Must also translate relative to base and rotate about connecting joint
- Upper arm attached to lower arm
  - Its position depends on both base and lower arm
  - Must translate relative to lower arm and rotate about joint connecting to lower arm

Required Matrices

- Rotation of base: $\mathbf{R}_b$
  - Apply $\mathbf{M} = \mathbf{R}_b$ to base
- Translate lower arm relative to base: $\mathbf{T}_{lu}$
- Rotate lower arm around joint: $\mathbf{R}_{lu}$
  - Apply $\mathbf{M} = \mathbf{R}_b\, \mathbf{T}_{lu}\, \mathbf{R}_{lu}$ to lower arm
- Translate upper arm relative to upper arm: $\mathbf{T}_{uu}$
- Rotate upper arm around joint: $\mathbf{R}_{uu}$
  - Apply $\mathbf{M} = \mathbf{R}_b\, \mathbf{T}_{lu}\, \mathbf{R}_{lu}\, \mathbf{T}_{uu}\, \mathbf{R}_{uu}$ to upper arm

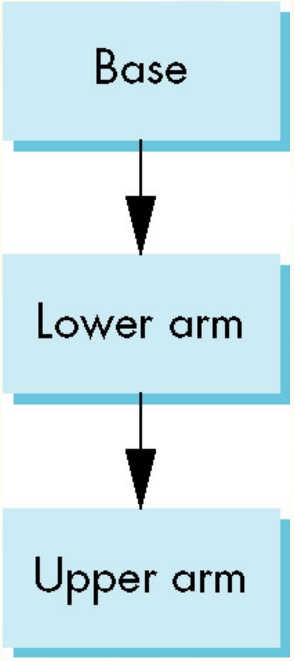
OpenGL Code for Robot

```
robot_arm(){
    glRotate(theta, 0.0, 1.0, 0.0);
    base();
    glTranslate(0.0, h1, 0.0);
    glRotate(phi, 0.0, 0.0, 1.0);
    lower_arm();
    glTranslate(0.0, h2, 0.0);
    glRotate(psi, 0.0, 0.0, 1.0);
    upper_arm();
}
```

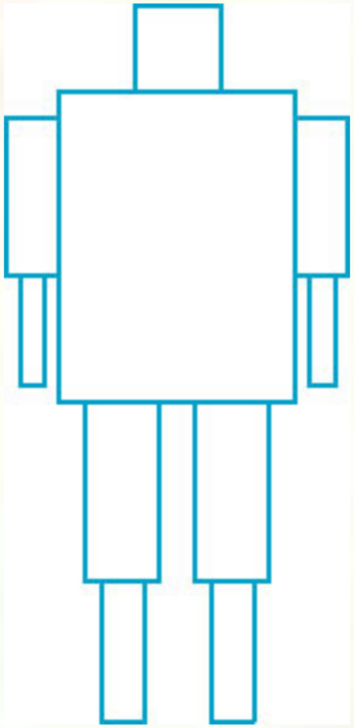
Tree Model of Robot

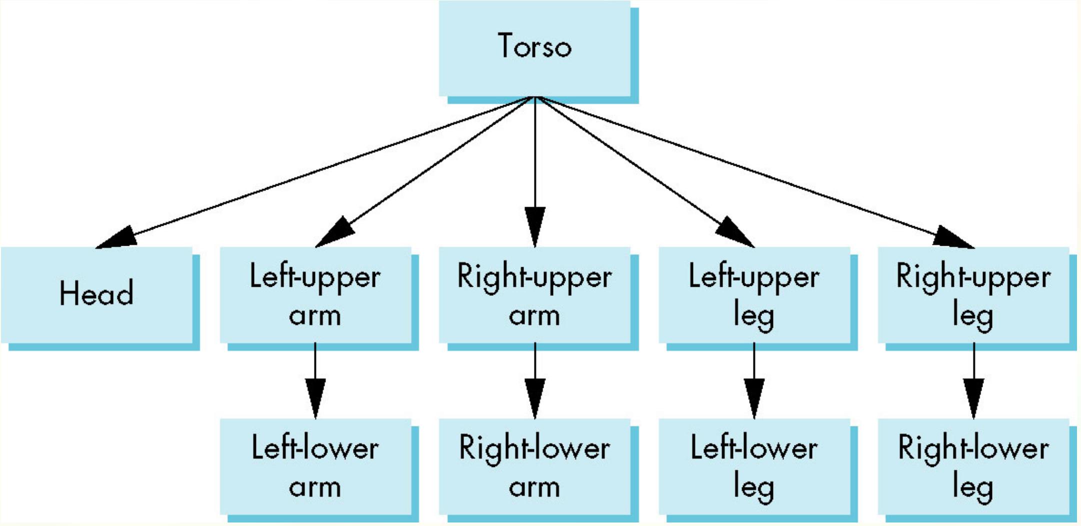
- Note code shows relationships between parts of model
  - Can change “look” of parts easily without altering relationships
- Simple example of tree model
- Want a general node structure

for nodes



Humanoid Figure

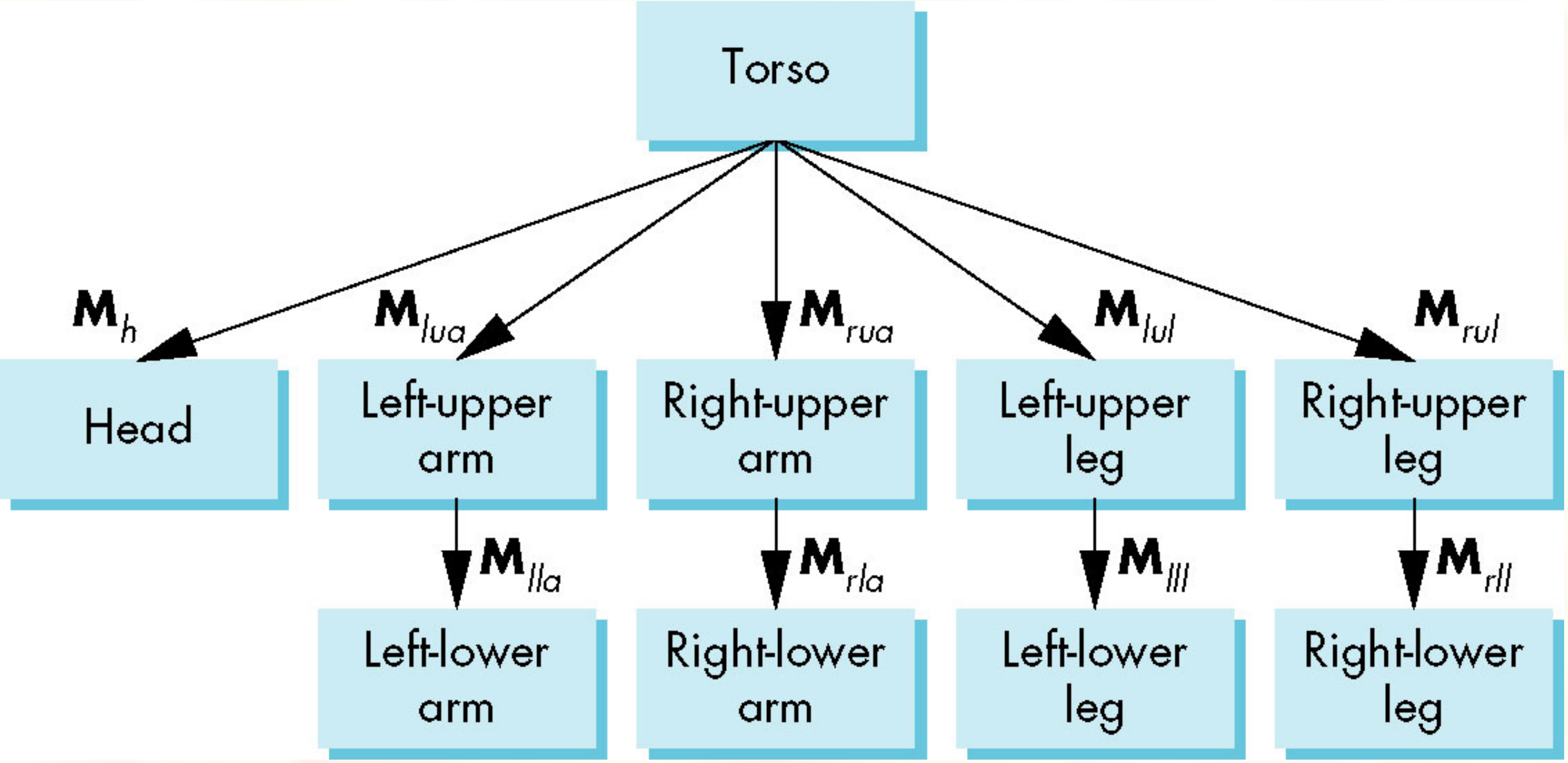




Building the Model

- Can build a simple implementation using quadrics: ellipsoids and cylinders
- Access parts through functions
  - `torso()`
  - `left_upper_arm()`
- Matrices describe position of node with respect to its parent
  - $\mathbf{M}_{lla}$ positions left lower leg with respect to left upper arm

Tree with Matrices



Display and Traversal

- The position of the figure is determined by 11 joint angles (two for the head and one for each other part)
- Display of the tree requires a *graph traversal*
  - Visit each node once
  - Display function at each node that describes the part associated with the node, applying the correct transformation matrix for position and orientation

Transformation Matrices

- There are 10 relevant matrices
  - **M** positions and orients entire figure through the torso which is the root node
  - $\mathbf{M}_{\mathrm{h}}$ positions head with respect to torso
  - $\mathbf{M}_{\mathrm{lua}}$, $\mathbf{M}_{\mathrm{rua}}$, $\mathbf{M}_{\mathrm{lul}}$, $\mathbf{M}_{\mathrm{rul}}$ position arms and legs with respect to torso
  - $\mathbf{M}_{\mathrm{lla}}$, $\mathbf{M}_{\mathrm{rla}}$, $\mathbf{M}_{\mathrm{lll}}$, $\mathbf{M}_{\mathrm{rll}}$ position lower parts of limbs with respect to corresponding upper limbs

Stack-based Traversal

- Set model-view matrix to **M** and draw torso
- Set model-view matrix to $\mathbf{MM}_h$ and draw head
- For left-upper arm need $\mathbf{MM}_{lua}$ and so on
- Rather than recomputing $\mathbf{MM}_{lua}$ from scratch or using an inverse matrix, we can use the matrix stack to store **M** and other matrices as we traverse the tree

Traversal Code

```
figure() {
    glPushMatrix()
    torso();
    glRotate3f(…);
    head();
    glPopMatrix();
    glPushMatrix();
    glTranslate3f(…);
    glRotate3f(…);
    left_upper_arm();
    glPopMatrix();
    glPushMatrix();
```

save present model-view matrix

update model-view matrix for head

recover original model-view matrix

save it again

update model-view matrix
for left upper arm

recover and save original
model-view matrix again

rest of code

Analysis

- The code describes a particular tree and a particular traversal strategy
  - Can we develop a more general approach?
- Note that the sample code does not include state changes, such as changes to colors
  - May also want to use **`glPushAttrib`** and **`glPopAttrib`** to protect against unexpected state changes affecting later parts of the code

Notes

- The position of figure is determined by 11 joint angles stored in **`theta[11]`**
- Animate by changing the angles and redisplaying
- We form the required matrices using **`glRotate`** and **`glTranslate`**
  - Because the matrix is formed in model-view matrix, we may want to first push original model-view matrix on matrix stack

Preorder Traversal

```
void traverse(treenode *root){
  if(root == NULL) return;
  glPushMatrix();
  glMultMatrix(root->m);
  root->f();
  if(root->child != NULL)
     traverse(root->child);
  glPopMatrix();
  if(root->sibling != NULL)
     traverse(root->sibling);
}
```

Notes

- We must save model-view matrix before multiplying it by node matrix
  - Updated matrix applies to children of node but not to siblings which contain their own matrices
- The traversal program applies to any left-child right-sibling tree
  - The particular tree is encoded in the definition of the individual nodes
- The order of traversal matters because of possible state changes in the functions

OpenGL and Objects

- OpenGL lacks an object orientation
- Consider, for example, a green sphere
  - We can model the sphere with polygons or use OpenGL quadrics
  - Its color is determined by the OpenGL state and is not a property of the object
- Defies our notion of a physical object
- We can try to build better objects in code using object-oriented languages/techniques

C/C++

- Can try to use C structs to build objects
- C++ provides better support
  - Use class construct
  - Can hide implementation using public, private, and protected members in a class
  - Can also use friend designation to allow classes to access each other

Cube Object

- Suppose that we want to create a simple cube object that we can scale, orient, position and set its color directly through code such as

```
cube mycube;
mycube.color[0]=1.0;
mycube.color[1]=
  mycube.color[2]=0.0;
mycube.matrix[0][0]=………
```

Cube Object Functions

- We would also like to have functions that act on the cube such as

```
mycube.translate(1.0, 0.0,0.0);
mycube.rotate(theta, 1.0, 0.0,
0.0);
setcolor(mycube, 1.0, 0.0, 0.0);
```

- We also need a way of displaying the cube

```
mycube.render();
```

Building the Cube Object

```
class cube {
   public:
      float color[3];
      float matrix[4][4];
   // public methods

   private:

   // implementation

}
```

The Implementation

- Can use any implementation in the private part such as a vertex list
- The private part has access to public members and the implementation of class methods can use any implementation without making it visible
- Render method is tricky but it will invoke the standard OpenGL drawing functions such as **`glVertex`**

Other Objects

- Other objects have geometric aspects
  - Cameras
  - Light sources
- But we should be able to have nongeometric objects too
  - Materials
  - Colors
  - Transformations (matrices)

Application Code

```
cube mycube;
material plastic;
mycube.setMaterial(plastic);

camera frontView;
frontView.position(x ,y, z);
```

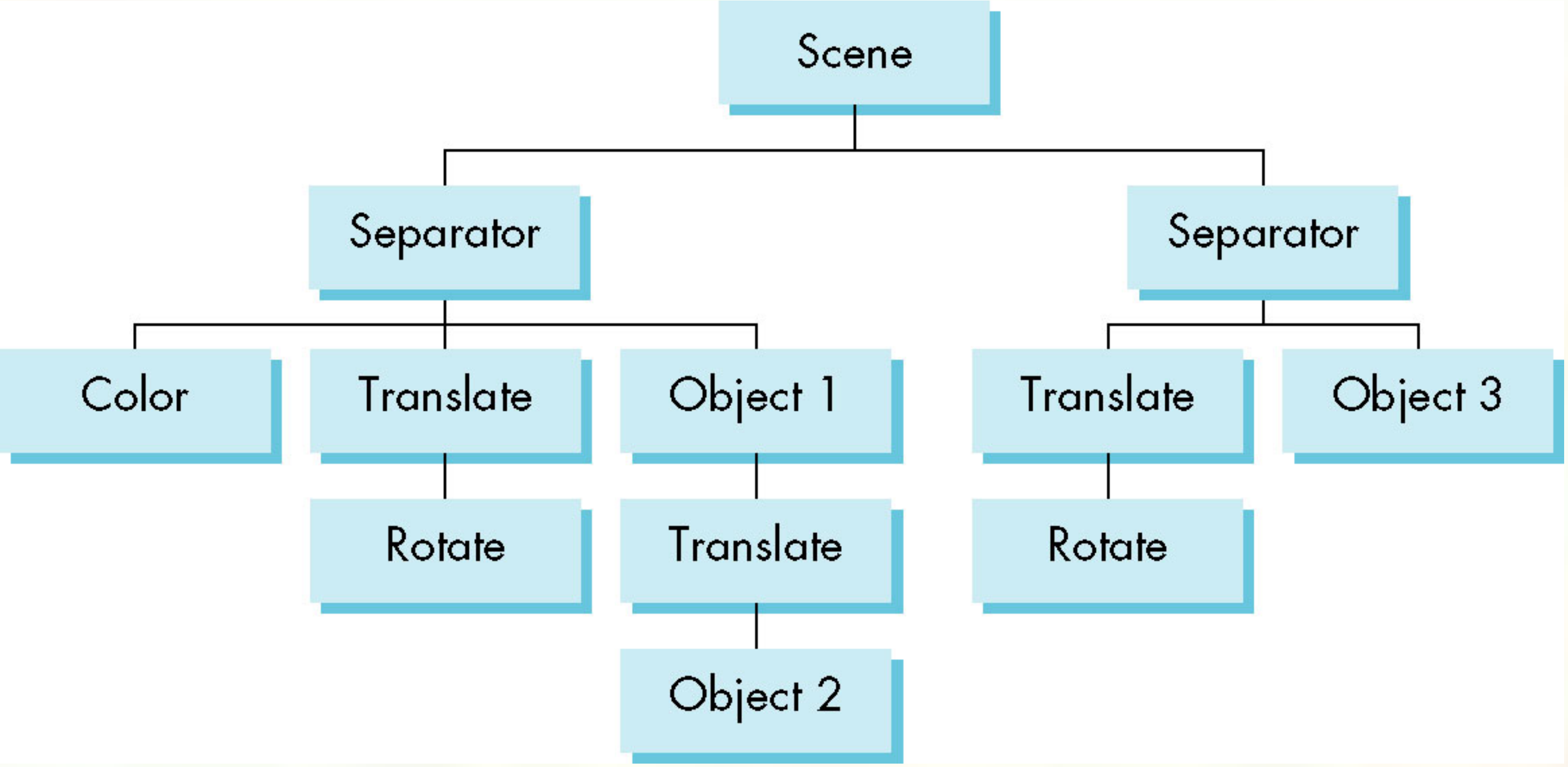
Light Object

```
class light {     // match Phong model
  public:
   boolean type; //ortho or perspective
   boolean near;
   float position[3];
   float orientation[3];
   float specular[3];
   float diffuse[3];
   float ambient[3];
}
```

Scene Descriptions

- If we recall figure model, we saw that
  - We could describe model either by tree or by equivalent code
  - We could write a generic traversal to display
- If we can represent all the elements of a scene (cameras, lights,materials, geometry) as C++ objects, we should be able to show them in a tree
  - Render scene by traversing this tree

Scene Graph


Scene
Separator
Separator
Color
Translate
Object 1
Translate
Object 3
Rotate
Translate
Rotate
Object 2

Preorder Traversal

```
glPushAttrib
glPushMatrix
glColor
glTranslate
glRotate
Object1
glTranslate
Object2
glPopMatrix
glPopAttrib
...
```

Separator Nodes

- Necessary to isolate state chages
    - Equivalent to OpenGL Push/Pop
- Note that as with the figure model
    - We can write a universal traversal algorithm
    - The order of traversal can matter
        - If we do not use the separator node, state changes can propagate

Inventor and Java3D

- Inventor and Java3D provide a scene graph API
- Scene graphs can also be described by a file (text or binary)
  - Implementation independent way of transporting scenes
  - Supported by scene graph APIs
- However, primitives supported should match capabilities of graphics systems
  - Hence most scene graph APIs are built on top of OpenGL or DirectX (for PCs)

VRML

- Want to have a scene graph that can be used over the World Wide Web
- Need links to other sites to support distributed data bases
- Virtual Reality Markup Language
  - Based on Inventor data base
  - Implemented with OpenGL