Undergraduate Topics in Computer Science

Undergraduate Topics in Computer Science' (UTiCS) delivers high-quality instructional content for undergraduates studying in all areas of computing and information science. From core foundational and theoretical material to final-year topics and applications, UTiCS books take a fresh, concise, and modern approach and are ideal for self-study or for a one- or two-semester course. The texts are all authored by established experts in their fields, reviewed by an international advisory board, and contain numerous examples and problems. Many include fully worked solutions.

For other volumes: http://www.springer.com/series/7592

Mathematics for Computer Graphics 3rd Edition



Prof. John Vince, MTech, PhD, DSc, CEng, FBCS www.johnvince.co.uk

Series editor

Advisory board
Samson Abramsky, University of Oxford, UK
Chris Hankin, Imperial College London, UK
Dexter Kozen, Cornell University, USA
Andrew Pitts, University of Cambridge, UK
Hanne Riis Nielson, Technical University of Denmark, Denmark
Steven Skiena, Stony Brook University, USA
Iain Stewart, University of Durham, UK
David Zhang, The Hong Kong Polytechnic University, Hong Kong

Undergraduate Topics in Computer Science ISSN 1863-7310 ISBN: 978-1-84996-022-9 e-ISBN: 978-1-84996-023-6

DOI: 10.1007/978-1-84996-023-6

Springer London Dordrecht Heidelberg New York

British Library Cataloguing in Publication Data A catalogue record for this book is available from the British Library

Library of Congress Control Number: 2009942716

© Springer-Verlag London Limited 2010

Apart from any fair dealing for the purposes of research or private study, or criticism or review, as permitted under the Copyright, Designs and Patents Act 1988, this publication may only be reproduced, stored or transmitted, in any form or by any means, with the prior permission in writing of the publishers, or in the case of reprographic reproduction in accordance with the terms of licenses issued by the Copyright Licensing Agency. Enquiries concerning reproduction outside those terms should be sent to the publishers.

The use of registered names, trademarks, etc., in this publication does not imply, even in the absence of a specific statement, that such names are exempt from the relevant laws and regulations and therefore free for general use.

The publisher makes no representation, express or implied, with regard to the accuracy of the information contained in this book and cannot accept any legal responsibility or liability for any errors or omissions that may be made.

Cover design: SPi Publisher Services

Printed on acid-free paper

Springer is part of Springer Science+Business Media (www.springer.com)



Preface

Mathematics is a beautiful subject. Its symbols, notation and abstract structures permit us to define, manipulate and resolve extremely complex problems. However, the symbols by themselves are meaningless – they are nothing more than a calligraphic representation of a mental idea. If one does not understand such symbols, then the encoded idea remains a secret.

Having spent most of my life using mathematics, I am still conscious of the fact that I do not understand much of the notation used by mathematicians. And even when I feel that I understand a type of notation, I still ask myself "Do I really understand its meaning?" For instance, I originally studied to be an electrical engineer and was very familiar with $i = \sqrt{-1}$, especially when used to represent out-of-phase voltages and currents. I can manipulate complex numbers with some confidence, but I must admit that I do not understand the physical meaning of i^i . This hole in my knowledge makes me feel uncomfortable, but I suppose it is reassuring to learn that some of our greatest mathematicians have had problems understanding some of their own inventions.

Some people working in computer graphics have had a rigorous grounding in mathematics and can exploit its power to solve their problems. However, in my experience, the majority of people have had to pick up their mathematical skills on an *ad hoc* basis depending on the problem at hand. They probably had no intention of being mathematicians, nevertheless they still had to study mathematics and apply it intelligently, which is where this book comes in.

To begin with, this book is not for mathematicians. They would probably raise their hands in horror about the level of mathematical rigour I have employed, or probably not employed! This book is for people working in computer graphics who know that they have to use mathematics in their day-to-day work, and don't want to get too embroiled in axioms, truths and Platonic realities.

This book originally appeared as part of Springer's excellent "Essential" series, and was revised to include chapters on analytical geometry, barycentric coordinates and worked examples. This edition includes a new chapter on geometric algebra, which I have written about in my books Geometric Algebra for Computer Graphics and Geometric Algebra: An Algebraic System for Computer Games and Animation.

viii Preface

Although I prepared the first book using Microsoft WORD, for this last edition I have used \LaTeX $2_{\mathcal{E}}$ which has greatly improved the layout. This, however, has required me to type in every equation again, which was not only tedious, but an opportunity to correct a handful of typos that always seem to find there way into books. I have also redrawn all the illustrations to bring a consistent graphical appearance to the book. \LaTeX $2_{\mathcal{E}}$ is an amazing software system – extremely fast and robust. The entire book only takes 4 s to typeset, which permitted me to edit the final draft and recompile every time I changed a single punctuation mark!

Whilst writing this book I have borne in mind what it was like for me when I was studying different areas of mathematics for the first time. In spite of reading and rereading an explanation several times it could take days before "the penny dropped" and a concept became apparent. Hopefully, the reader will find the following explanations useful in developing their understanding of these specific areas of mathematics, and enjoy the sound of various pennies dropping!

Once again, I am indebted to Beverley Ford, General Manager, Springer UK, and Helen Desmond, Assistant Editor for Computer Science, for persuading me to give up holidays and hobbies in order to complete this book! I would also like to thank Springer's technical support team for their help with LATEX 2ε .

Ringwood, January 2010 John Vince

Contents

1	Math	ematics 1
	1.1	Introduction
	1.2	Is Mathematics Difficult?
	1.3	Who Should Read This Book?
	1.4	Aims and Objectives of This Book
	1.5	Assumptions Made in This Book
	1.6	How to Use This Book
2	Numl	bers 5
	2.1	Introduction
	2.2	Natural Numbers
	2.3	Prime Numbers
	2.4	Integers
	2.5	Rational Numbers 7
	2.6	Irrational Numbers
	2.7	Real Numbers
	2.8	The Number Line
	2.9	Complex Numbers
	2.10	Summary
3	Algeb	ora
	3.1	Introduction
	3.2	Notation
	3.3	Algebraic Laws
		3.3.1 Associative Law
		3.3.2 Commutative Law
		3.3.3 Distributive Law
	3.4	Solving the Roots of a Quadratic Equation
	3.5	Indices
		3.5.1 Laws of Indices
		3.5.2 Examples

x Contents

	3.6	Logari	ithms	18
	3.7	_	r Notation	19
	3.8	Summ	ary	19
4	Trigo	nometry	y	21
	4.1	Introd	uction	21
	4.2	The Ti	rigonometric Ratios	22
	4.3	Examp	ole	23
	4.4	Inverse	e Trigonometric Ratios	23
	4.5	Trigon	nometric Relationships	23
	4.6		ne Rule	24
	4.7	The Co	osine Rule	24
	4.8	Comp	ound Angles	25
	4.9	Perime	eter Relationships	25
	4.10		ary	26
5	Carta	ocion Co	ordinates	27
3	5.1		uction	27
	5.2		artesian xy-Plane	27
	3.2	5.2.1	Function Graphs	28
		5.2.1	Geometric Shapes	29
		5.2.3		29
		5.2.3	Polygonal Shapes	30
			Areas of Shapes	
	<i>5</i> 2	5.2.5	Theorem of Pythagoras in 2D	31
	5.3	5.3.1	ordinates	31 33
			Theorem of Pythagoras in 3D	
		5.3.2	3D Polygons	33
	5.4	5.3.3	Euler's Rule	33 33
	3.4	Sullilli	ary	33
6				35
	6.1		uction	35
	6.2		ctors	36
		6.2.1	Vector Notation	36
		6.2.2	Graphical Representation of Vectors	37
		6.2.3	Magnitude of a Vector	38
	6.3		ctors	39
		6.3.1	Vector Manipulation	40
		6.3.2	Multiplying a Vector by a Scalar	40
		6.3.3	Vector Addition and Subtraction	41
		6.3.4	Position Vectors	42
		6.3.5	Unit Vectors	43
		6.3.6	Cartesian Vectors	44
		6.3.7	Vector Multiplication	45
		6.3.8	Scalar Product	45

Contents xi

		6.3.9	Example of the Scalar Product	47
		6.3.10	The Dot Product in Lighting Calculations	48
		6.3.11	The Scalar Product in Back-Face Detection	49
		6.3.12	The Vector Product	50
		6.3.13	The Right-Hand Rule	54
	6.4	Derivir	ng a Unit Normal Vector for a Triangle	55
	6.5	Areas .		55
		6.5.1	Calculating 2D Areas	56
	6.6	Summa	ary	57
7	Trans	sforms		59
	7.1	Introdu	action	59
	7.2	2D Tra	nsforms	59
		7.2.1	Translation	59
		7.2.2	Scaling	60
		7.2.3	Reflection	60
	7.3	Matrice	es	62
		7.3.1	Systems of Notation	64
		7.3.2	The Determinant of a Matrix	65
	7.4	Homog	geneous Coordinates	65
		7.4.1	2D Translation	67
		7.4.2	2D Scaling	67
		7.4.3	2D Reflections	68
		7.4.4	2D Shearing	70
		7.4.5	2D Rotation	70
		7.4.6	2D Scaling	73
		7.4.7	2D Reflection	73
		7.4.8	2D Rotation About an Arbitrary Point	74
	7.5	3D Tra	nsforms	75
		7.5.1	3D Translation	75
		7.5.2	3D Scaling	76
		7.5.3	3D Rotation	76
		7.5.4	Gimbal Lock	80
		7.5.5	Rotating About an Axis	81
		7.5.6	3D Reflections	83
	7.6	Change	e of Axes	83
		7.6.1	2D Change of Axes	83
		7.6.2	Direction Cosines	85
		7.6.3	3D Change of Axes	86
	7.7		ning the Virtual Camera	87
		7.7.1	Direction Cosines	87
		7.7.2	Euler Angles	90
	7.8	Rotatin	ng a Point About an Arbitrary Axis	93
		7.8.1	Matrices	93
		782	Quaternions	99

xii Contents

		7.8.3 Adding and Subtracting Quaternions	
		7.8.4 Multiplying Quaternions	1
		7.8.5 Pure Quaternion	1
		7.8.6 The Inverse Quaternion	
		7.8.7 Unit Quaternion	2
		7.8.8 Rotating Points About an Axis	2
		7.8.9 Roll, Pitch and Yaw Quaternions	6
		7.8.10 Quaternions in Matrix Form	7
		7.8.11 Frames of Reference	8
	7.9	Transforming Vectors	9
	7.10	Determinants	1
	7.11	Perspective Projection	
	7.12	Summary	7
8	Interp	polation11	9
	8.1	Introduction	9
	8.2	Linear Interpolation	9
	8.3	Non-Linear Interpolation	2
		8.3.1 Trigonometric Interpolation	2
		8.3.2 Cubic Interpolation	3
	8.4	Interpolating Vectors	
	8.5	Interpolating Quaternions	1
	8.6	Summary	3
9	Curve	es and Patches	5
	9.1	Introduction	5
	9.2	The Circle	5
	9.3	The Ellipse	6
	9.4	Bézier Curves	7
		9.4.1 Bernstein Polynomials	7
		9.4.2 Quadratic Bézier Curves	1
		9.4.3 Cubic Bernstein Polynomials	2
	9.5	A Recursive Bézier Formula	5
	9.6	Bézier Curves Using Matrices	5
		9.6.1 Linear Interpolation	6
	9.7	B-Splines	9
		9.7.1 Uniform B-Splines	0
		9.7.2 Continuity	2
		9.7.3 Non-uniform B-Splines	
		9.7.4 Non-uniform Rational B-Splines	
	9.8	Surface Patches	
		9.8.1 Planar Surface Patch	4
		9.8.2 Quadratic Bézier Surface Patch	5
		9.8.3 Cubic Bézier Surface Patch	
	9.9	Summary	

Contents xiii

10	Analy	tic Geon	netry	161
	10.1		ction	
	10.2	Review	of Geometry	
		10.2.1	Angles	161
		10.2.2	Intercept Theorems	162
		10.2.3	Golden Section	163
		10.2.4	Triangles	163
		10.2.5	Centre of Gravity of a Triangle	164
		10.2.6	Isosceles Triangle	164
		10.2.7	Equilateral Triangle	165
		10.2.8	Right Triangle	
		10.2.9	Theorem of Thales	165
		10.2.10	Theorem of Pythagoras	166
		10.2.11	Quadrilaterals	166
		10.2.12	Trapezoid	167
		10.2.13	Parallelogram	167
		10.2.14	Rhombus	168
		10.2.15	Regular Polygon (n-gon)	168
		10.2.16	Circle	168
	10.3	2D Ana	alytic Geometry	170
		10.3.1	Equation of a Straight Line	170
		10.3.2	The Hessian Normal Form	171
		10.3.3	Space Partitioning	173
		10.3.4	The Hessian Normal Form from Two Points	
	10.4	Intersec	ction Points	
		10.4.1	Intersection Point of Two Straight Lines	
		10.4.2	Intersection Point of Two Line Segments	
	10.5	Point In	nside a Triangle	178
		10.5.1	Area of a Triangle	
		10.5.2	Hessian Normal Form	180
	10.6	Intersec	ction of a Circle with a Straight Line	182
	10.7	3D Geo	ometry	
		10.7.1	Equation of a Straight Line	
		10.7.2	Point of Intersection of Two Straight Lines	
	10.8	Equation	on of a Plane	
		10.8.1	Cartesian Form of the Plane Equation	
		10.8.2	General Form of the Plane Equation	190
		10.8.3		
		10.8.4	Converting from the Parametric to the General Form	192
		10.8.5	Plane Equation from Three Points	193
	10.9	Intersec	cting Planes	
		10.9.1	Intersection of Three Planes	199
		10.9.2	Angle Between Two Planes	
		10.9.3	Angle between a Line and a Plane	203
		10.9.4	Intersection of a Line with a Plane	204
	10.10	Summa	rv	206

xiv Contents

11	Baryc	entric Coordinates	07
	11.1	Introduction	07
	11.2	Ceva's Theorem	07
	11.3	Ratios and Proportion	09
	11.4	Mass Points	10
	11.5	Linear Interpolation	
	11.6	Convex Hull Property	23
	11.7	Areas	23
	11.8	Volumes	32
	11.9	Bézier Curves and Patches	34
	11.10	Summary	35
12	Geom	etric Algebra2.	37
	12.1	Introduction	
	12.2	Symmetric and Antisymmetric Functions	
	12.3	Trigonometric Foundations	
	12.4	Vectorial Foundations	
	12.5	Inner and Outer Products	
	12.6	The Geometric Product in 2D	42
	12.7	The Geometric Product in 3D	
	12.8	The Outer Product of Three 3D Vectors	46
	12.9	Axioms	48
	12.10	Notation	48
	12.11	Grades, Pseudoscalars and Multivectors	49
	12.12	Redefining the Inner and Outer Products	50
	12.13	The Inverse of a Vector	50
	12.14	The Imaginary Properties of the Outer Product	52
	12.15	Duality	54
	12.16	The Relationship Between the Vector Product and the Outer	
		Product	55
	12.17	The Relationship Between Quaternions and Bivectors 25	55
	12.18	Reflections and Rotations	56
		12.18.1 2D Reflections	57
		12.18.2 3D Reflections	57
		12.18.3 2D Rotations	58
	12.19	Rotors	60
	12.20	Applied Geometric Algebra	64
		12.20.1 Sine Rule	64
		12.20.2 Cosine Rule	65
		12.20.3 A Point Perpendicular to a Point on a Line	65
		12.20.4 Reflecting a Vector about a Vector	
		12.20.5 Orientation of a Point with a Plane	
	12.21	Summary	70

Contents xv

13	Work	ed Examples	. 271
	13.1	Introduction	
	13.2	Area of Regular Polygon	. 271
	13.3	Area of any Polygon	
	13.4	Dihedral Angle of a Dodecahedron	. 273
	13.5	Vector Normal to a Triangle	. 274
	13.6	Area of a Triangle Using Vectors	. 275
	13.7	General Form of the Line Equation from Two Points	. 275
	13.8	Angle Between Two Straight Lines	. 276
	13.9	Test if Three Points Lie on a Straight Line	. 277
	13.10	Position and Distance of the Nearest Point on a Line to a Point	. 278
	13.11	Position of a Point Reflected in a Line	. 280
	13.12	Intersection of a Line and a Sphere	. 282
	13.13	Sphere Touching a Plane	. 286
	13.14	Summary	. 288
14	Concl	usion	. 289
Ind	ex		. 291