6.837 Computer Graphics Hierarchical Modeling

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Some slides from BarbCutler & Jaakko Lehtinen

Recap

- Vectors can be expressed in a basis
  - Keep track of basis with left notation $\vec{v} = \vec{\mathbf{b}}^t \mathbf{c}$
  - Change basis $\vec{v} = \vec{\mathbf{a}}^t M^{-1} \mathbf{c}$
- Points can be expressed in a frame (origin+basis)
  - Keep track of frame with left notation
  - adds a dummy 4th coordinate always 1

$$\tilde{p} = \tilde{o} + \sum_i c_i \vec{b}_i = \begin{bmatrix} \vec{b}_1 & \vec{b}_2 & \vec{b}_3 & \tilde{o} \end{bmatrix} \begin{bmatrix} c_1 \\ c_2 \\ c_3 \\ 1 \end{bmatrix} = \vec{\mathbf{f}}^t \mathbf{c}$$

Frames & transformations

- Transformation S wrt car frame f

$$\tilde{p} = \vec{\mathbf{f}}^t \mathbf{c} \Rightarrow \vec{\mathbf{f}}^t S \mathbf{c}$$

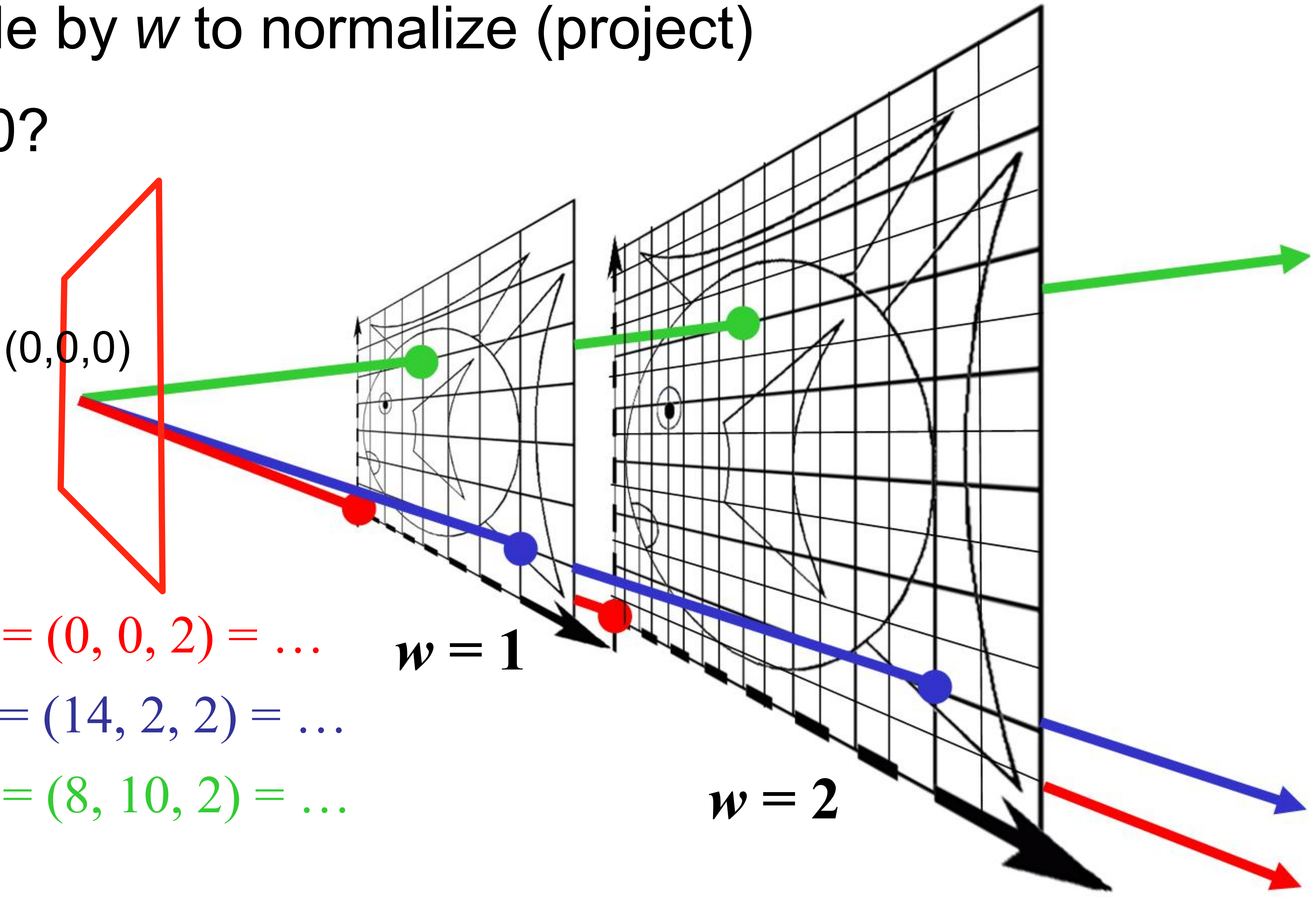
- how is the world frame a affected by this?
- *we have* $\vec{a}^t = \vec{f}^t A \quad \vec{\mathbf{f}}^t = \vec{\mathbf{a}}^t A^{-1}$
- *which gives* $\vec{a}^t A^{-1} \Rightarrow \vec{a}^t A^{-1} S$

$$\vec{a}^t \Rightarrow \vec{a}^t A^{-1} S A$$

- *i.e. the transformation in a is A-1SA*
- *i.e., from right to left, A takes us from a to f, then we apply S, then we go back to a with A-1*

Homogeneous Visualization

- Divide by *w* to normalize (project)
- *w* = 0?



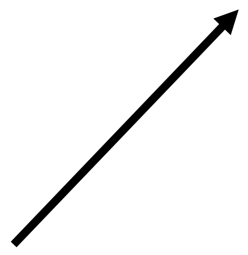
(0, 0, 1) = (0, 0, 2) = …

(7, 1, 1) = (14, 2, 2) = …

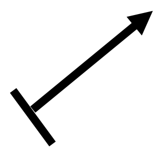
(4, 5, 1) = (8, 10, 2) = …

Different objects

- **Points**
  - represent locations



- **Vectors**
  - represent movement, force, displacement from A to B
- **Normals**
  - represent orientation, unit length

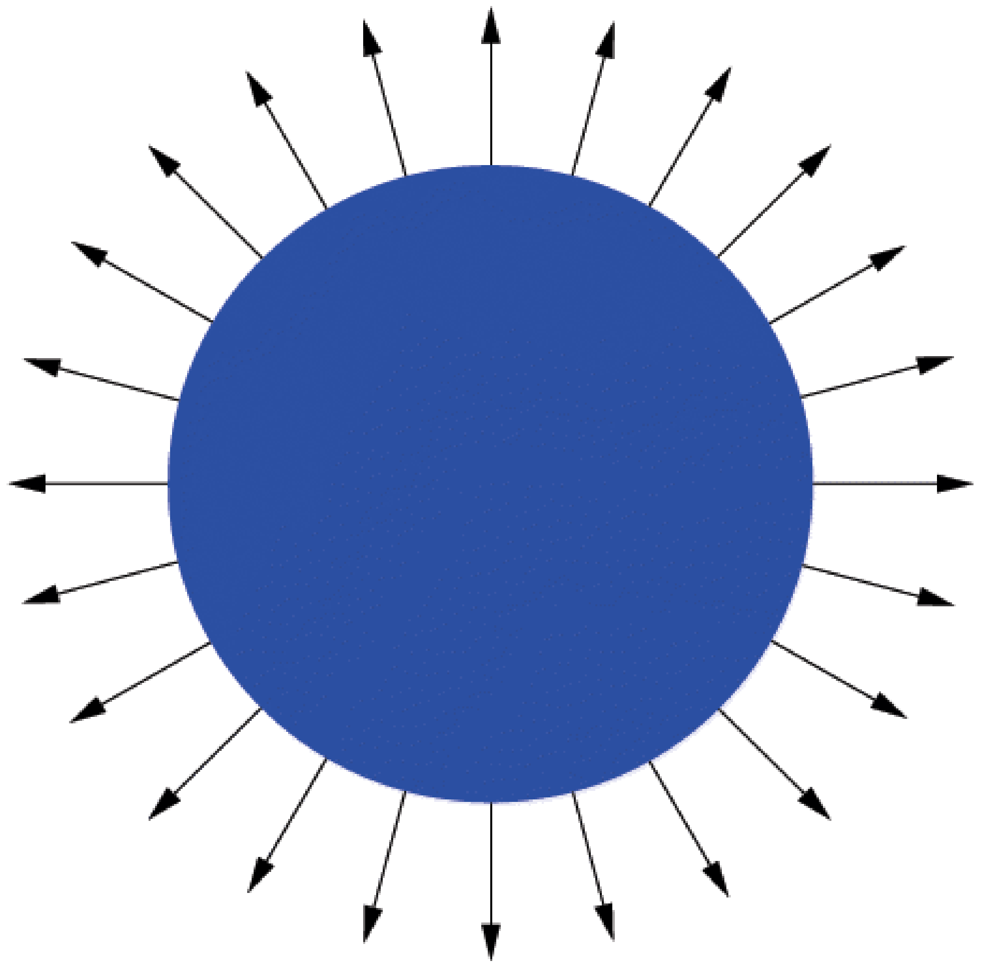
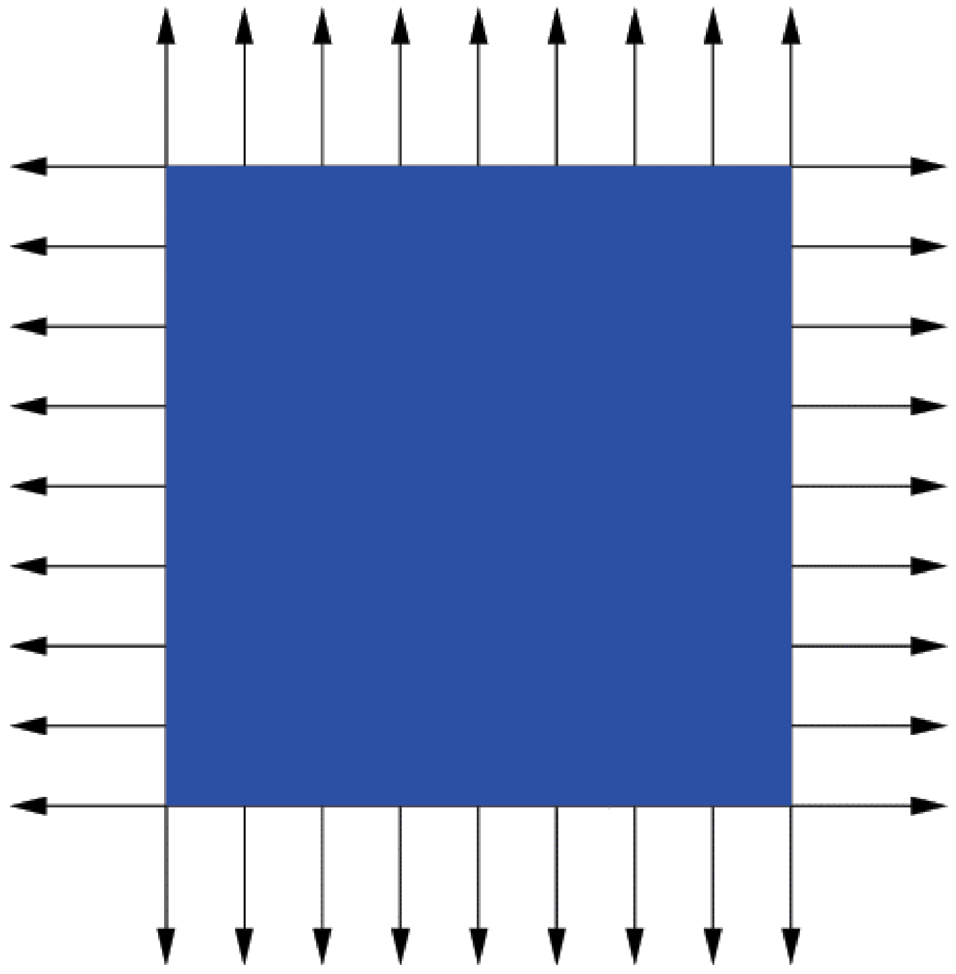


- **Coordinates**
  - numerical representation of the above objects **in a given coordinate system**

$$\begin{pmatrix} 1 \\ 2 \end{pmatrix}$$

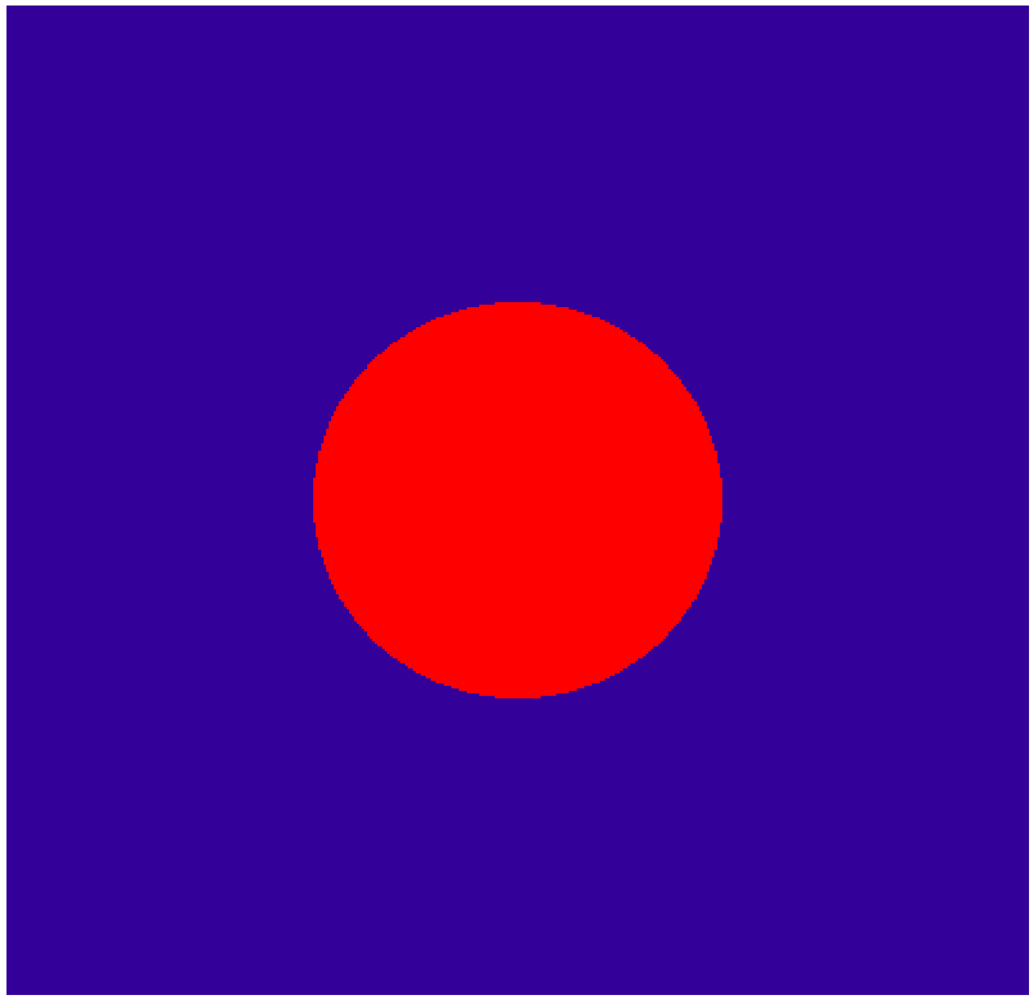
Normal

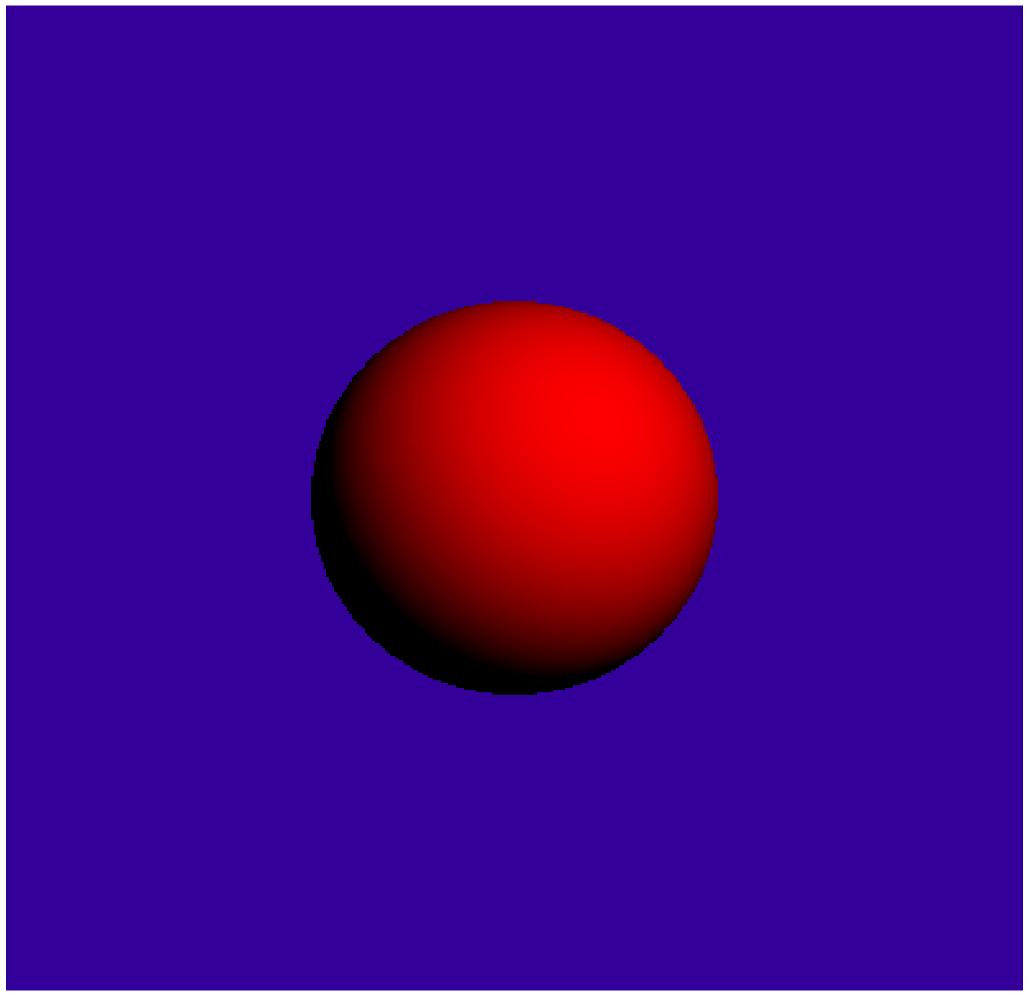
- Surface Normal: unit vector that is locally perpendicular to the surface

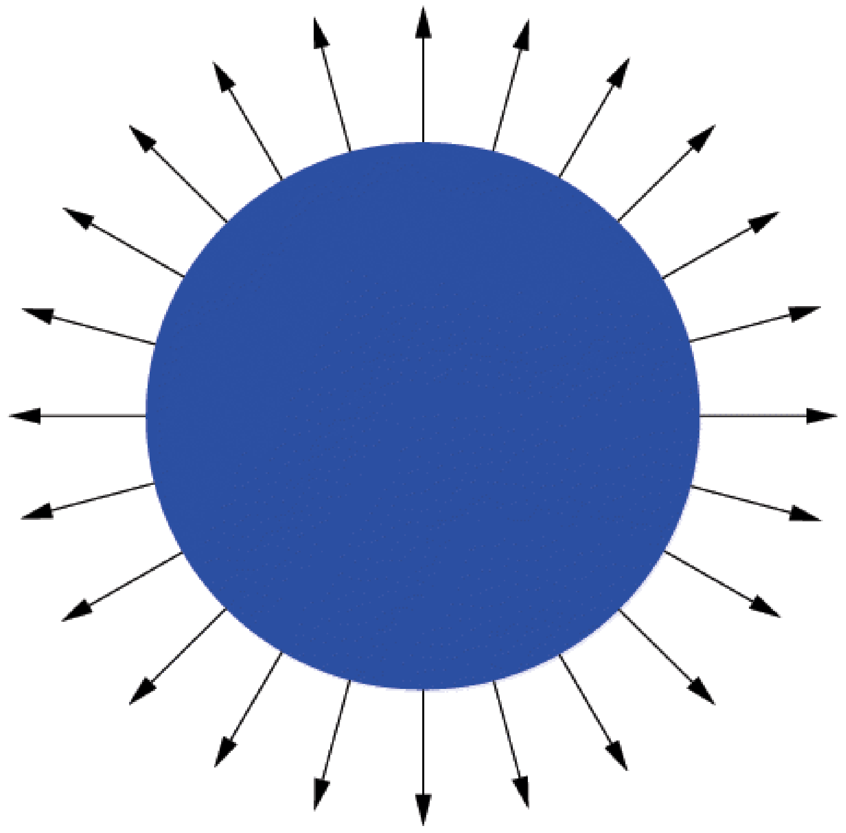
Why is the Normal important?

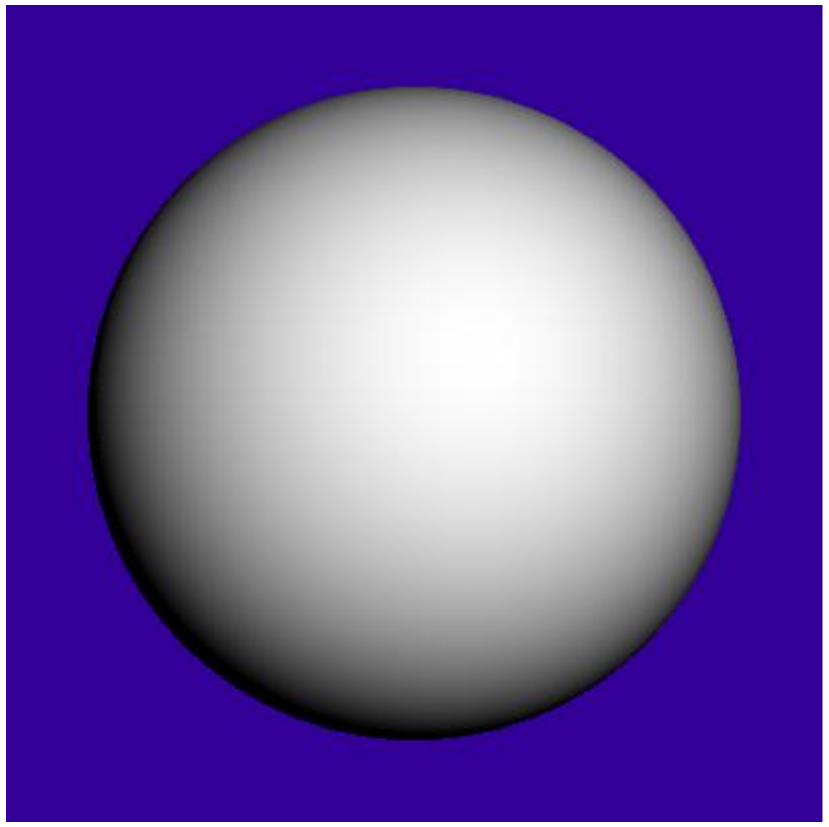
- It's used for shading — makes things look 3D!

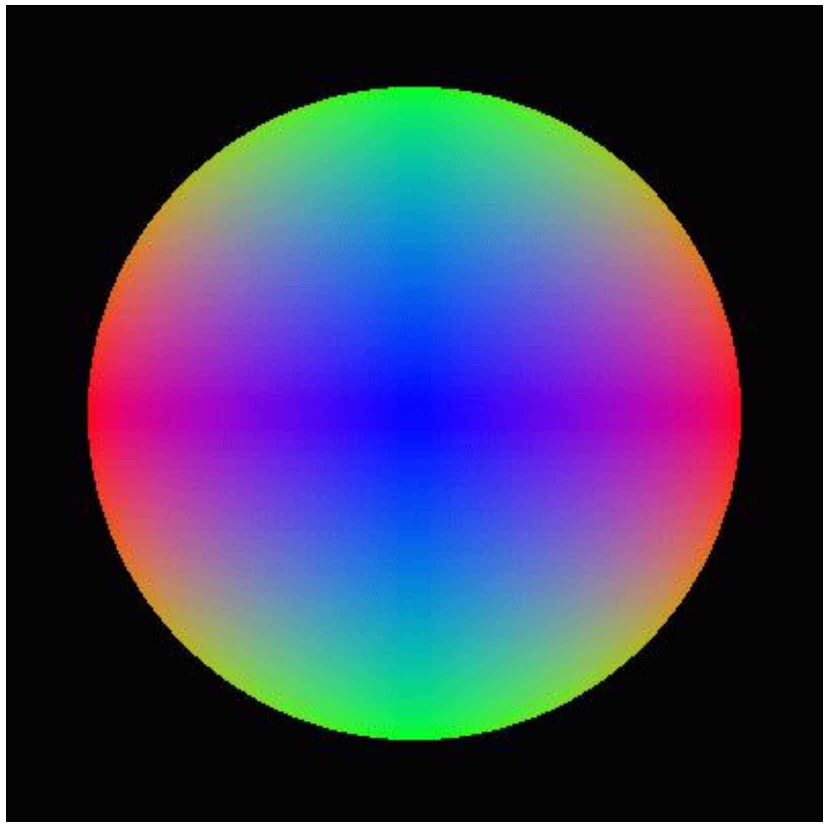

object color only


Diffuse Shading

Visualization of Surface Normal





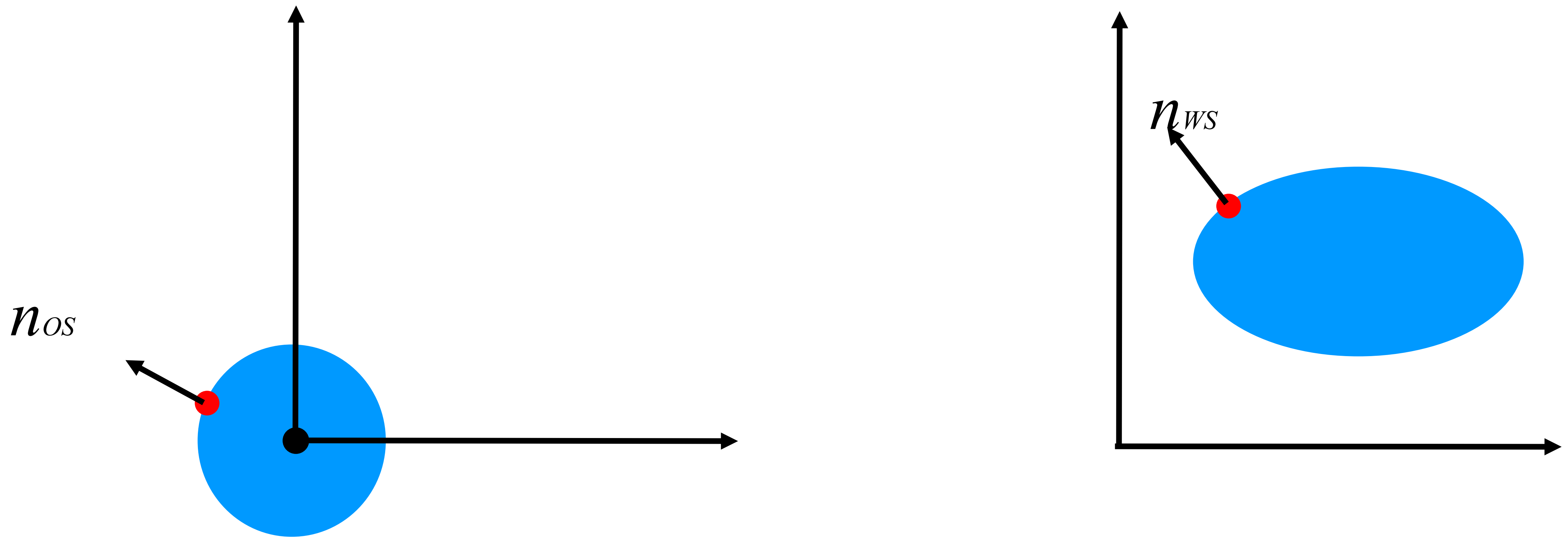


$\pm x$ = Red

$\pm y$ = Green

$\pm z$ = Blue

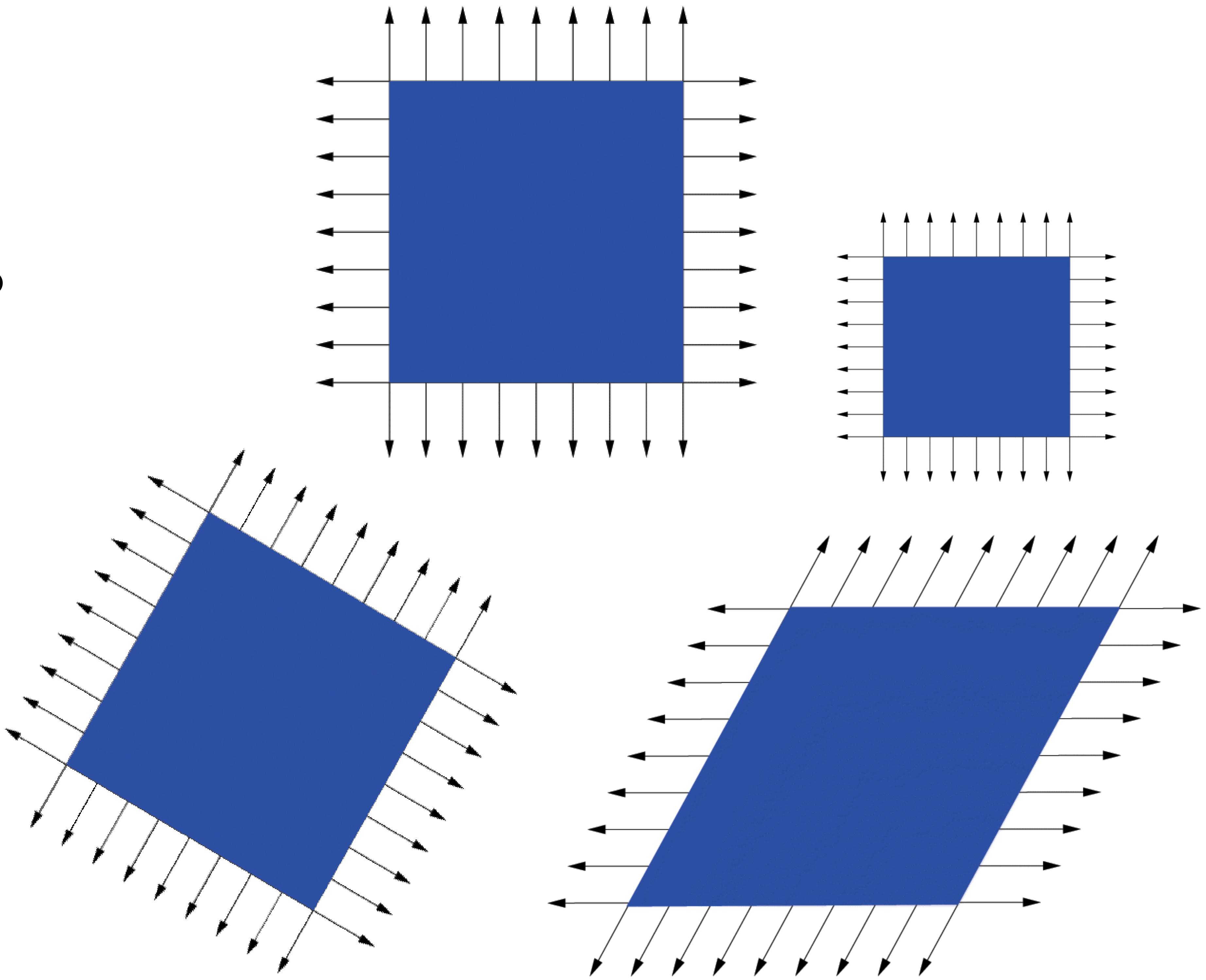
How do we transform normals?



Object Space **World Space**

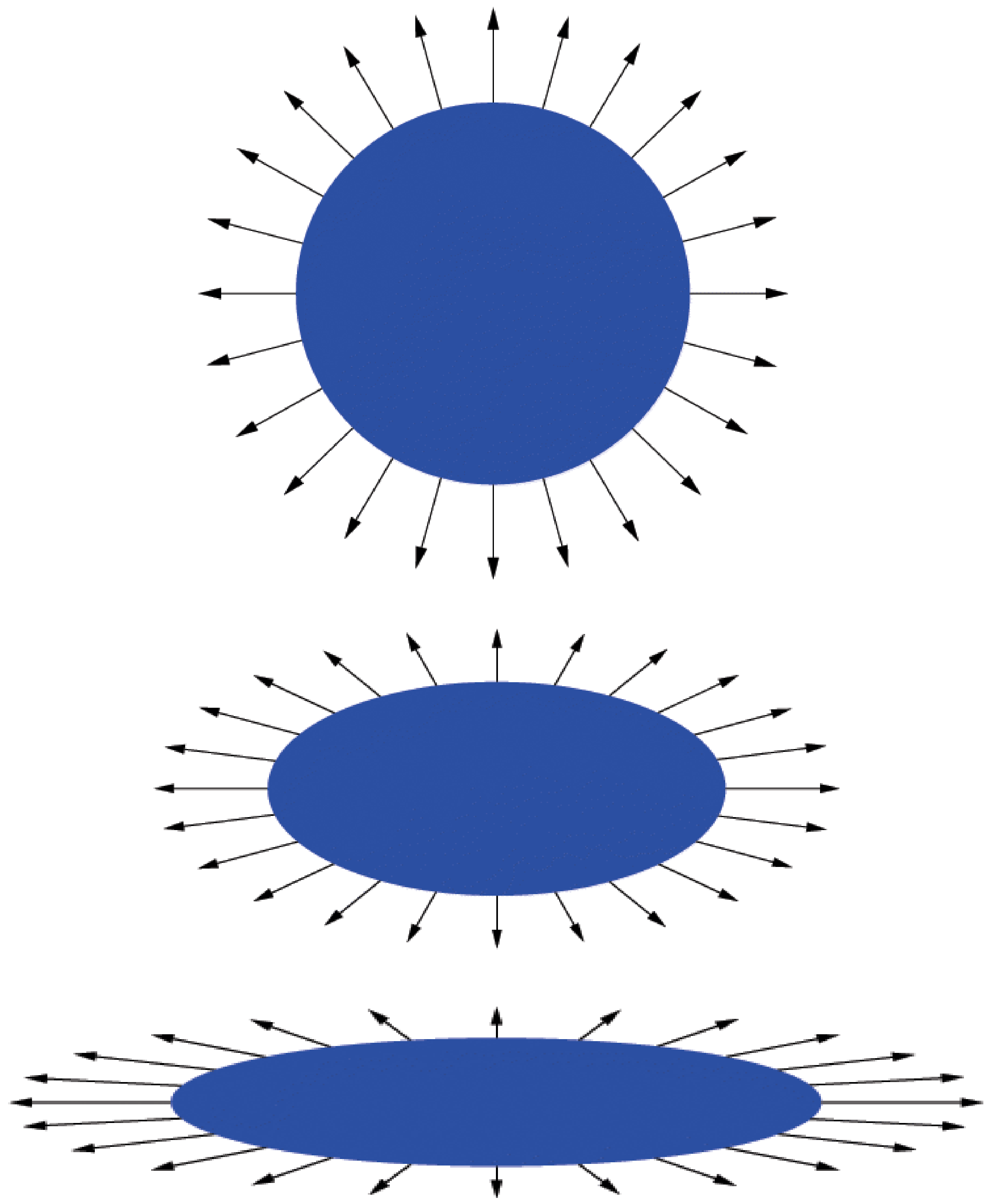
Transform Normal like Object?

- translation?
- rotation?
- isotropic scale?
- scale?
- reflection?
- shear?
- perspective?



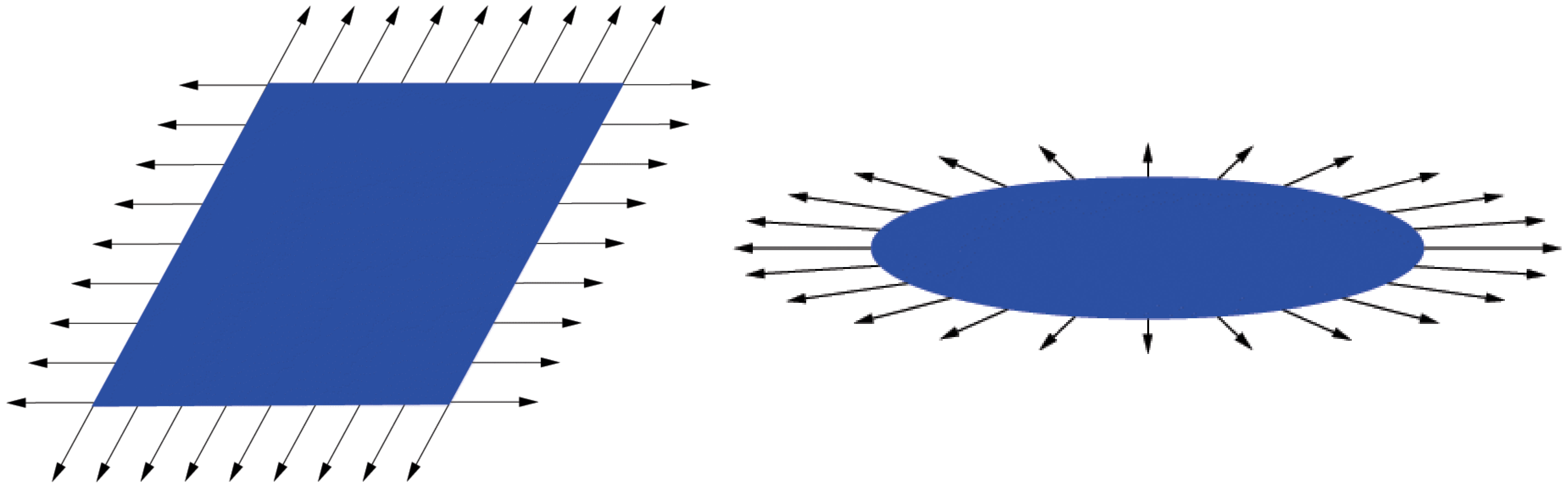
Transform Normal like Object?

- translation?
- rotation?
- isotropic scale?
- scale?
- reflection?
- shear?
- perspective?

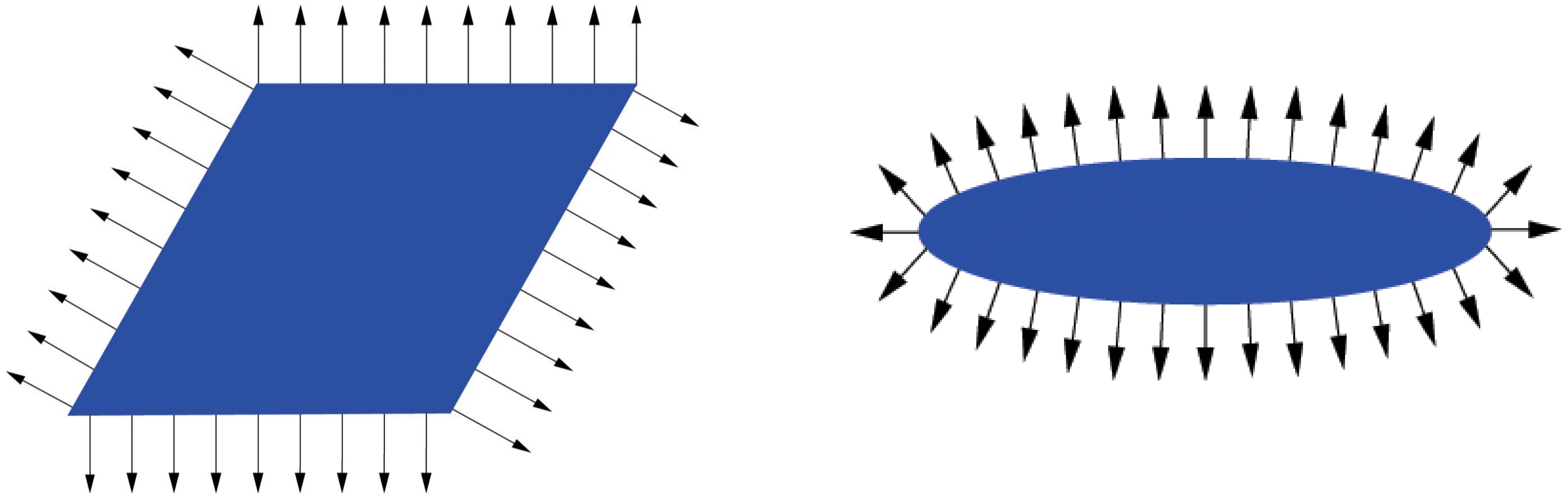


Transformation for shear and scale

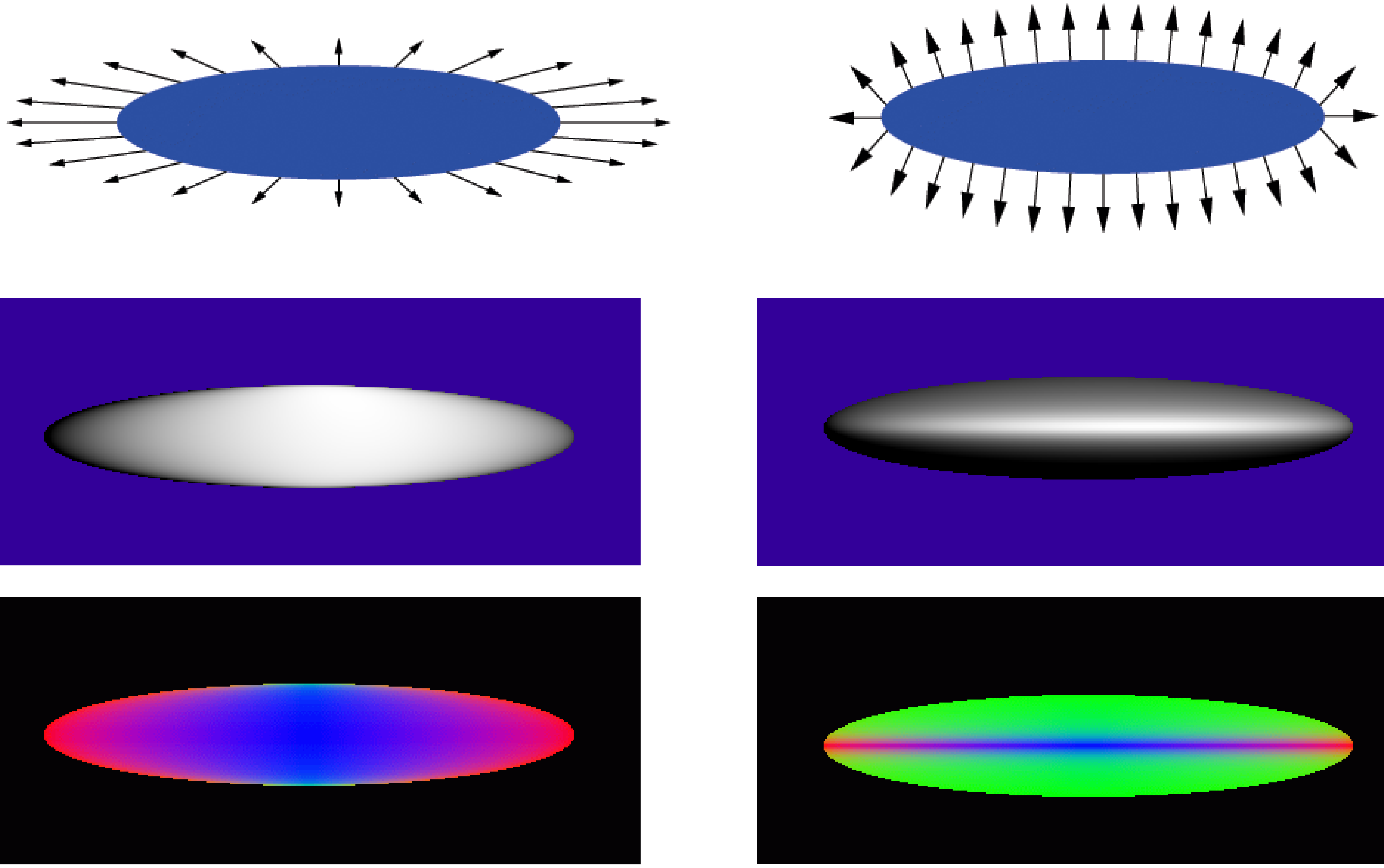
Incorrect
Normal
Transformation



Correct
Normal
Transformation



More Normal Visualizations

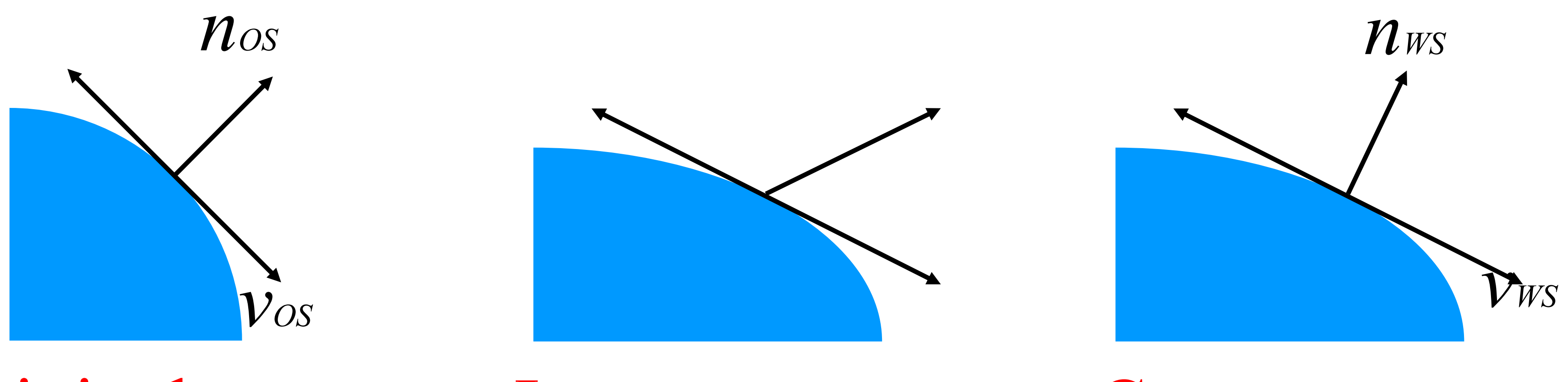


Incorrect Normal Transformation

Correct Normal Transformation

So how do we do it right?

- Think about transforming the *tangent plane* to the normal, not the normal *vector*



Original Incorrect Correct

Pick any vector *vOS* in the tangent plane, how is it transformed by matrix **M**?

$$v_{WS} = \mathbf{M} \, v_{OS}$$

Transform tangent vector *v*

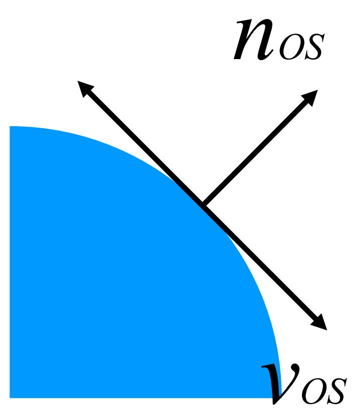
v is perpendicular to normal *n*:

Dot product $n_{os}^{\mathsf{T}}\, v_{os} = 0$

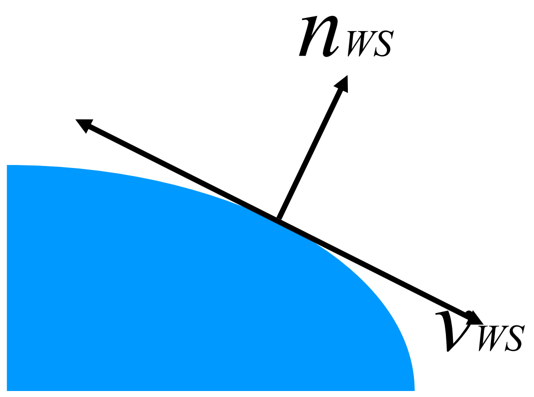
$$n_{os}^{\mathsf{T}}\ (\mathbf{M}^{-1}\ \mathbf{M})\ v_{os} = 0$$

$$(n_{os}^{\mathsf{T}}\ \mathbf{M}^{-1})\ (\mathbf{M}\ \ v_{os}) = 0$$

$$(n_{os}^{\mathsf{T}}\ \mathbf{M}^{-1})\ v_{ws} = 0$$



v_{ws} is perpendicular to normal n_{ws}:



$$n_{ws}^{\mathsf{T}} = n_{os}^{\mathsf{T}}\,(\mathbf{M}^{-1})$$

$$\boxed{n_{ws} = (\mathbf{M}^{-1})^{\mathsf{T}}\, n_{os}}$$

$$n_{ws}^{\mathsf{T}}\, v_{ws} = 0$$

Digression

$$\boxed{n_{WS} = (\mathbf{M}^{-1})^{\mathsf{T}} n_{OS}}$$

- The previous proof is not quite rigorous; first you’d need to prove that tangents indeed transform with **M**.
  - Turns out they do, but we’ll take it on faith here.
  - If you believe that, then the above formula follows.

Comment

- So the correct way to transform normals is:

$$n_{WS} = (\mathbf{M}^{-1})^{\mathsf{T}}\, n_{OS}$$ Sometimes denoted $\mathrm{M}^{-\mathrm{T}}$

- But why did $n_{WS} = \mathbf{M}\, n_{OS}$ work for similitudes?
- Because for similitude / similarity transforms,

$$(\mathbf{M}^{-1})^{\mathsf{T}} = \lambda\, \mathbf{M}$$

- e.g. for orthonormal basis:

$$\mathbf{M}^{-1} = \mathbf{M}^{\mathsf{T}} \quad \text{i.e.} \quad (\mathbf{M}^{-1})^{\mathsf{T}} = \mathbf{M}$$

Connections

- Not part of class, but cool
  - “Covariant”: transformed by the matrix
    - e.g., tangent
  - “Contravariant”: transformed by the inverse transpose
    - e.g., the normal
    - a normal is a “co-vector”

- Google “differential geometry” to find out more

- Further Reading
  - Buss, Chapter 2

- Other Cool Stuff
  - Algebraic Groups
  - http://phototour.cs.washington.edu/
  - http://phototour.cs.washington.edu/findingpaths/
  - Free-form deformation of solid objects
  - Harmonic coordinates for character articulation

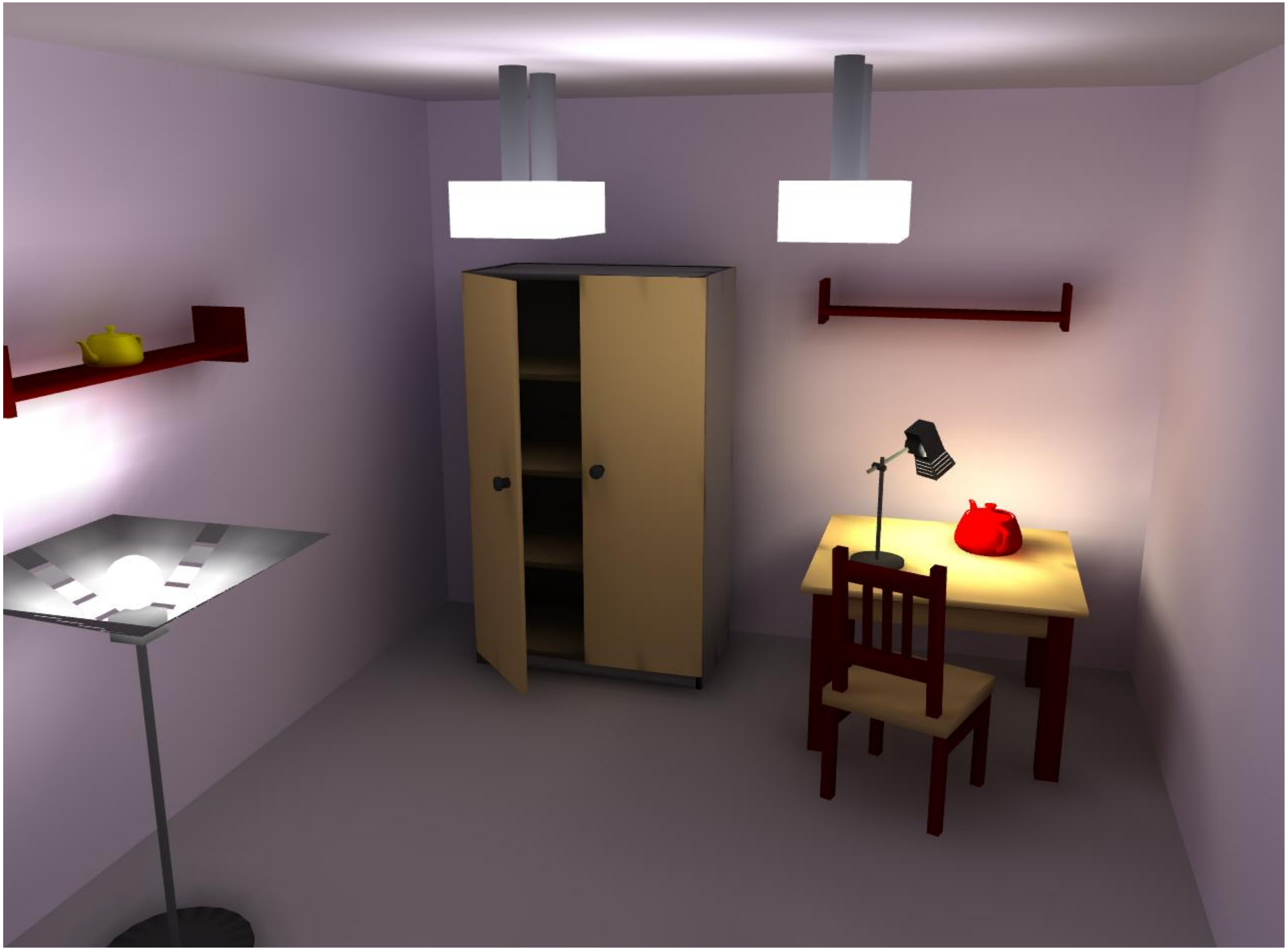
Question?

Hierarchical Modeling

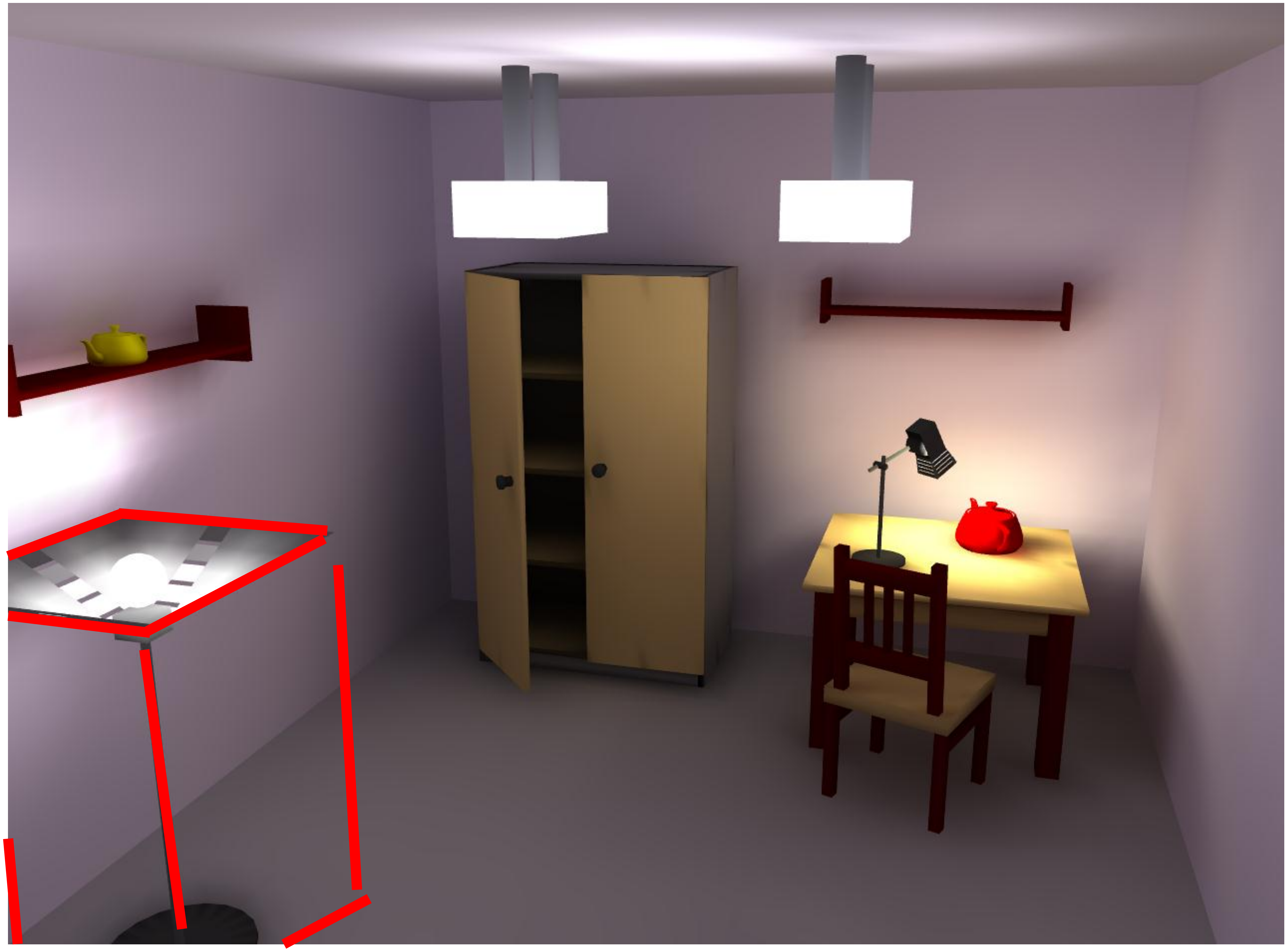
- Triangles, parametric curves and surfaces are the building blocks from which more complex real-world objects are modeled.

- Hierarchical modeling creates complex real-world objects by combining simple primitive shapes into more complex aggregate objects.

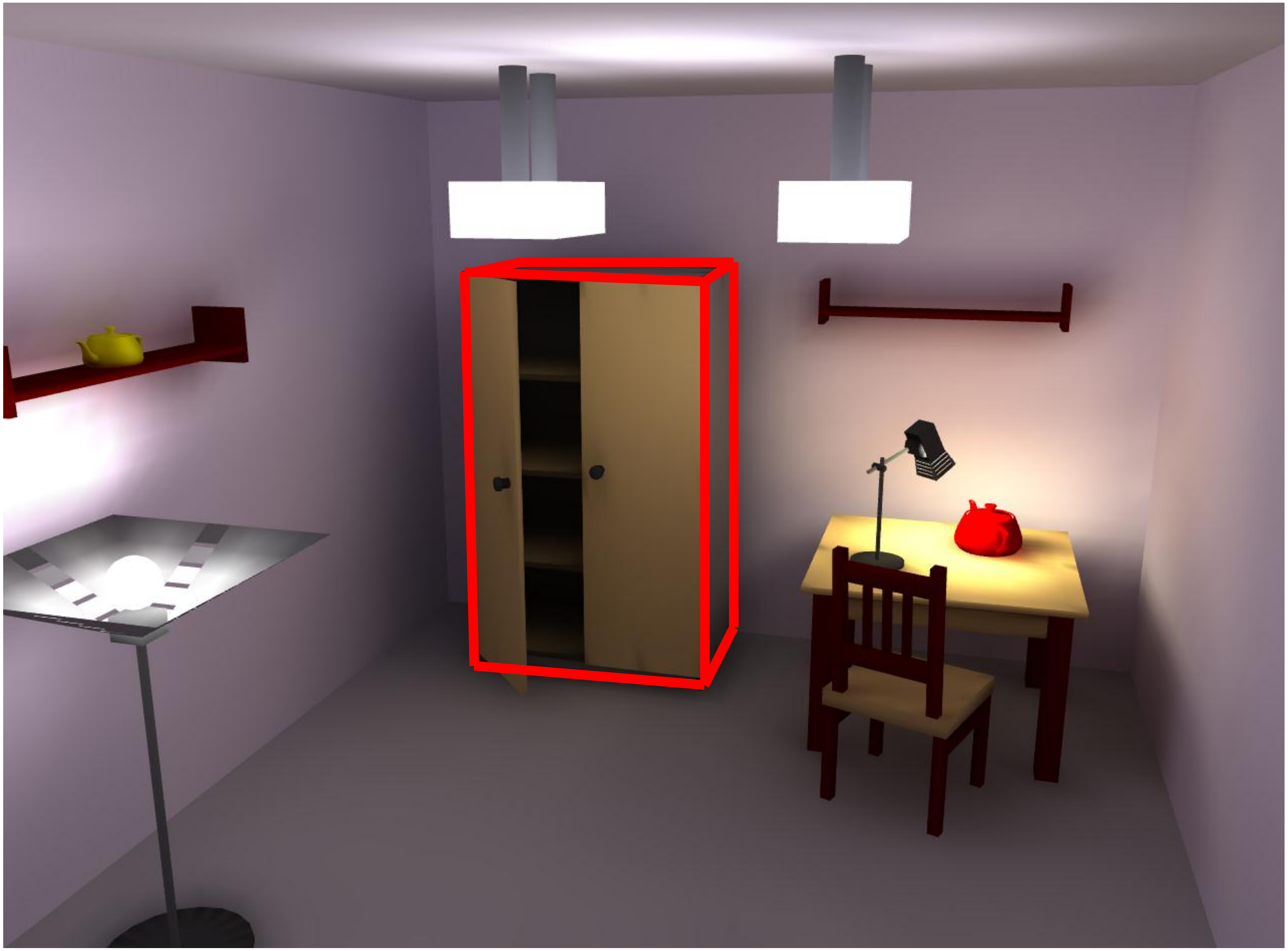
Hierarchical models



Hierarchical models



Hierarchical models



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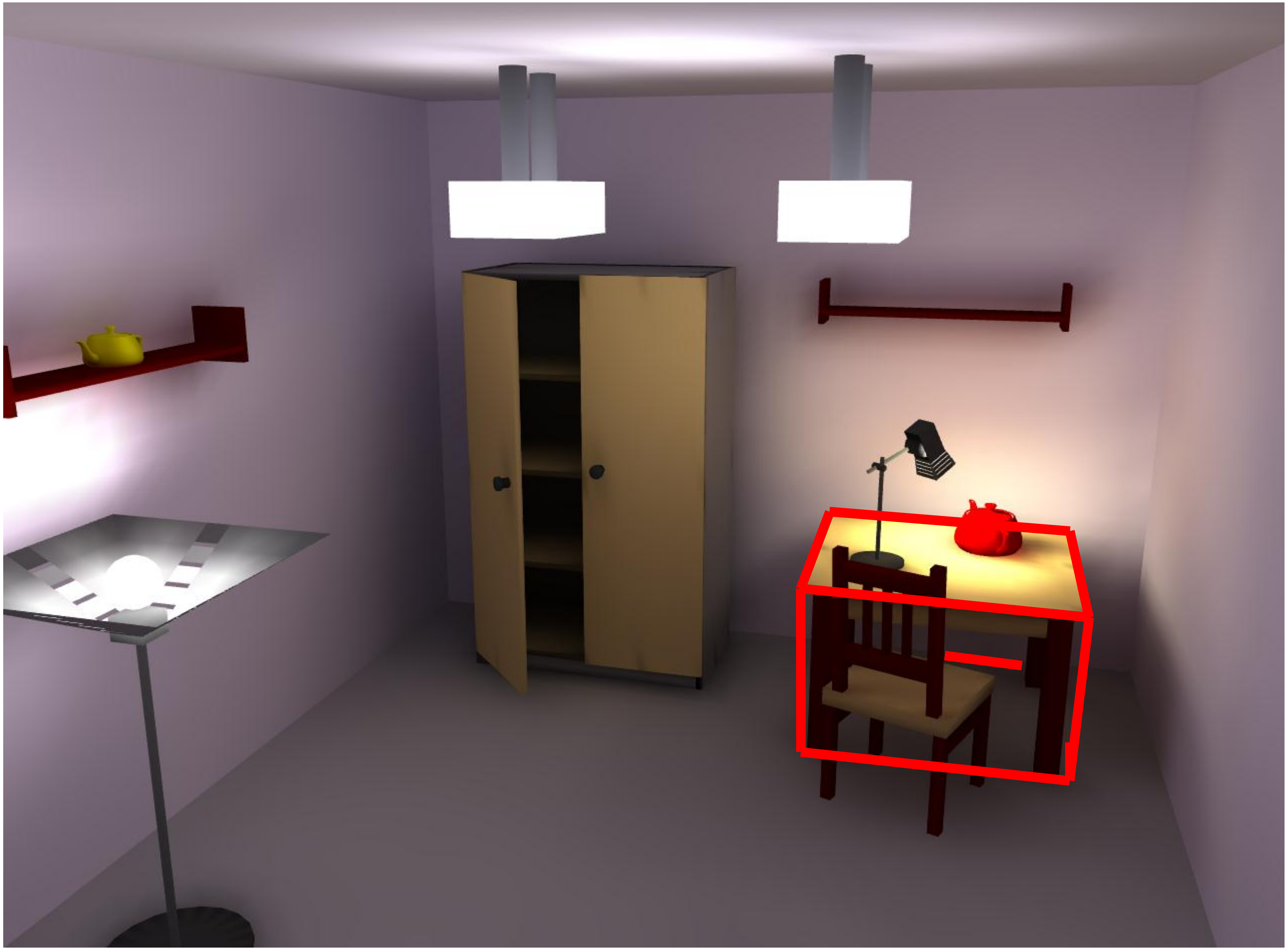
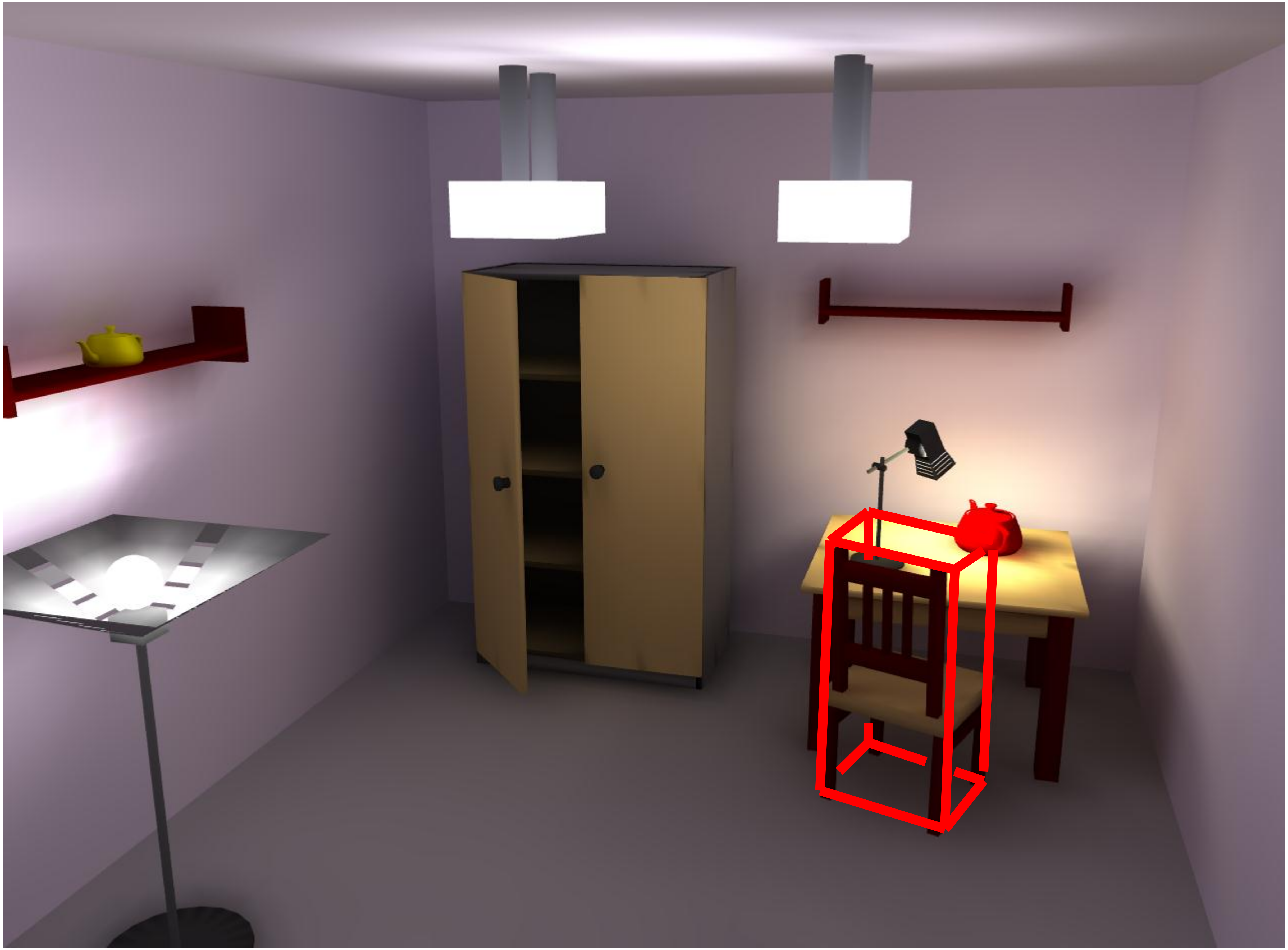
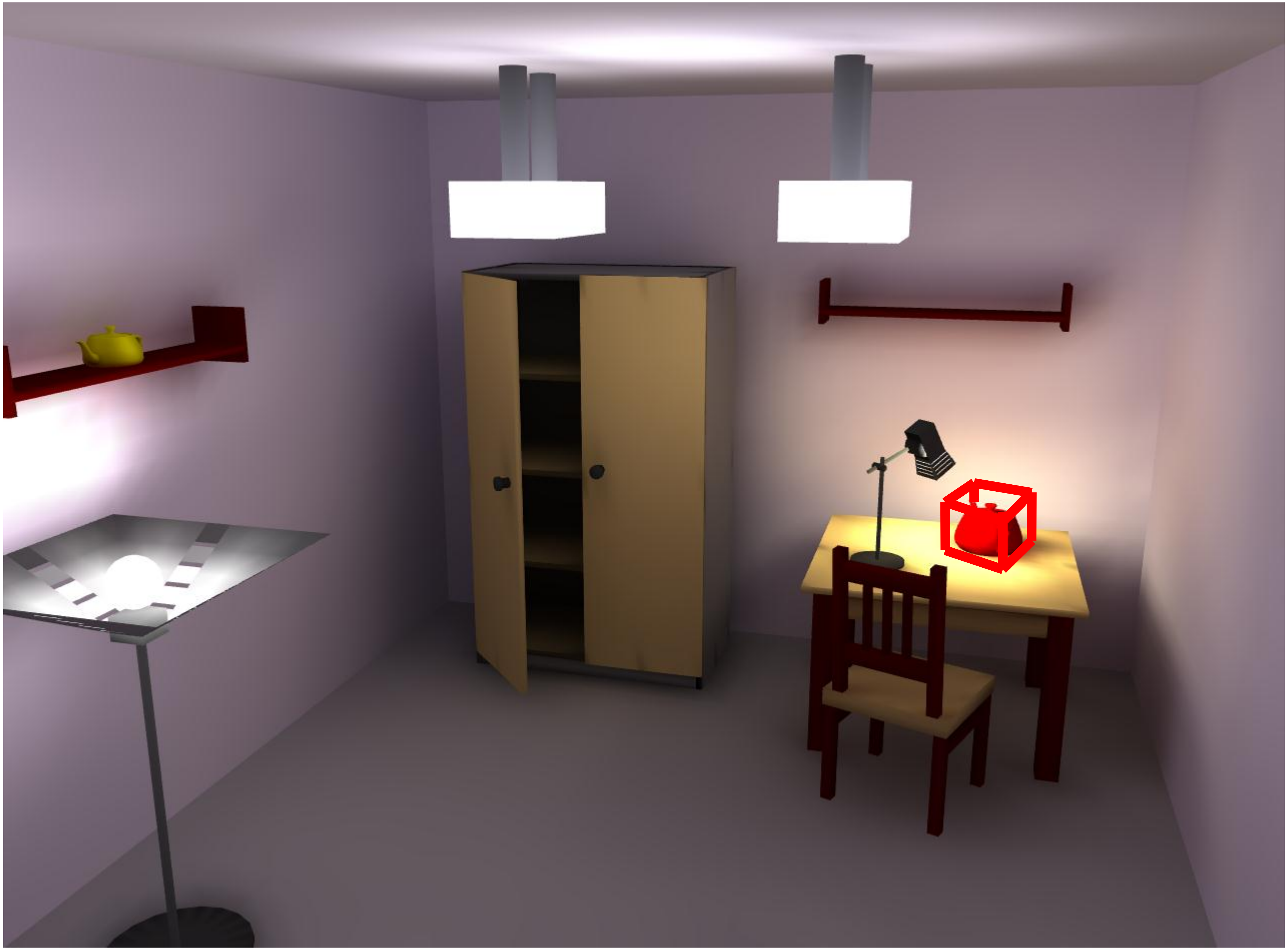
Hierarchical models



Hierarchical models

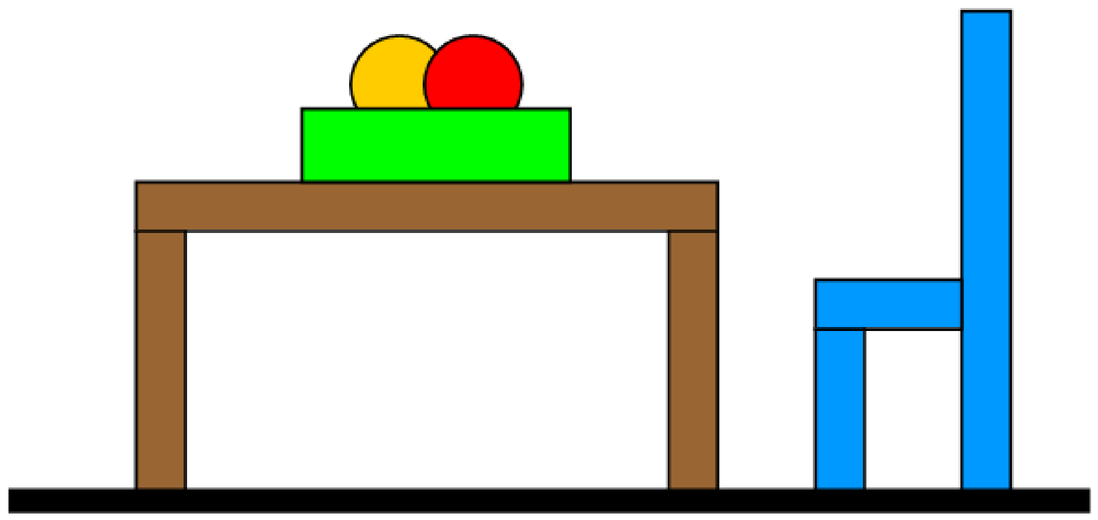


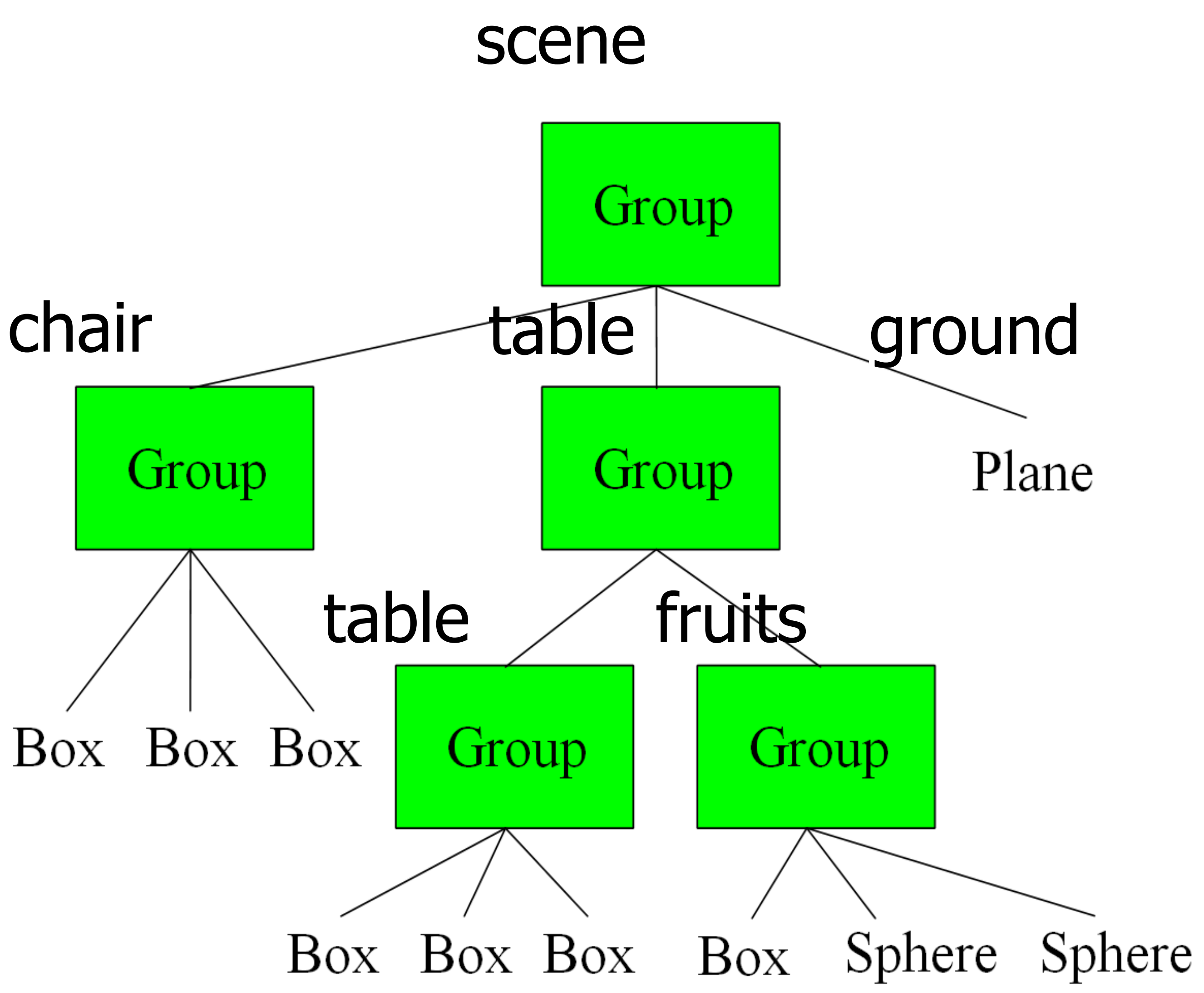
Hierarchical models



Hierarchical Grouping of Objects

- The "scene graph" represents the logical organization of scene

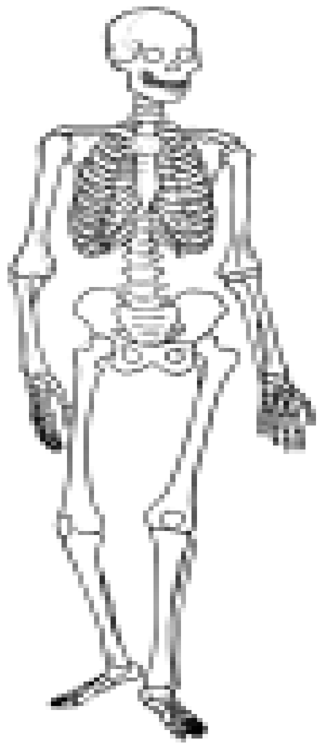




Scene Graph

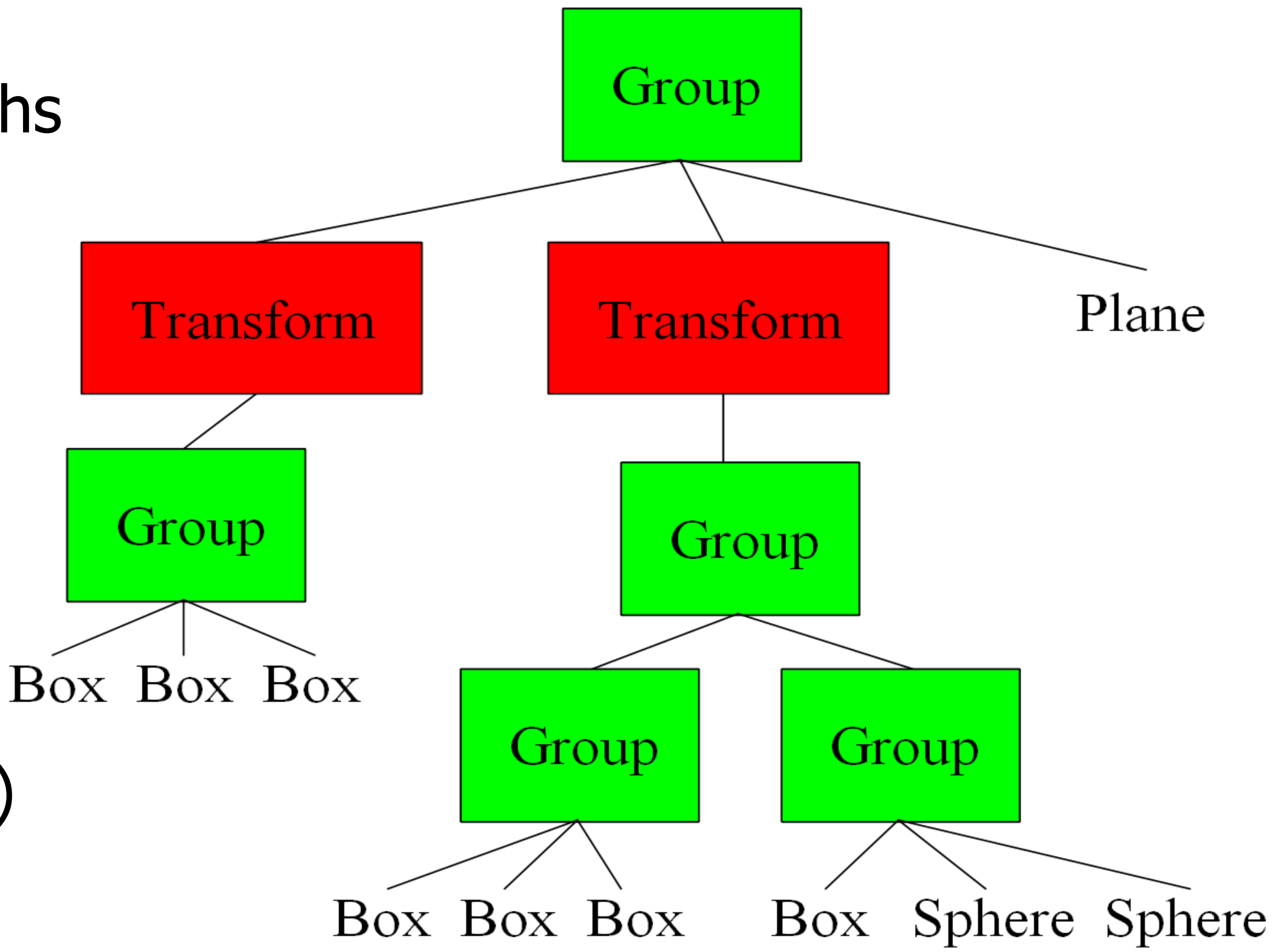
- Convenient Data structure for scene representation
  - Geometry (meshes, etc.)
  - Transformations
  - Materials, color
  - Multiple instances

- Basic idea: Hierarchical Tree
- Useful for manipulation/animation
  - Also for articulated figures
- Useful for rendering, too
  - Ray tracing acceleration, occlusion culling
  - But note that two things that are close to each other in the tree are NOT necessarily spatially near each other



Scene Graph Representation

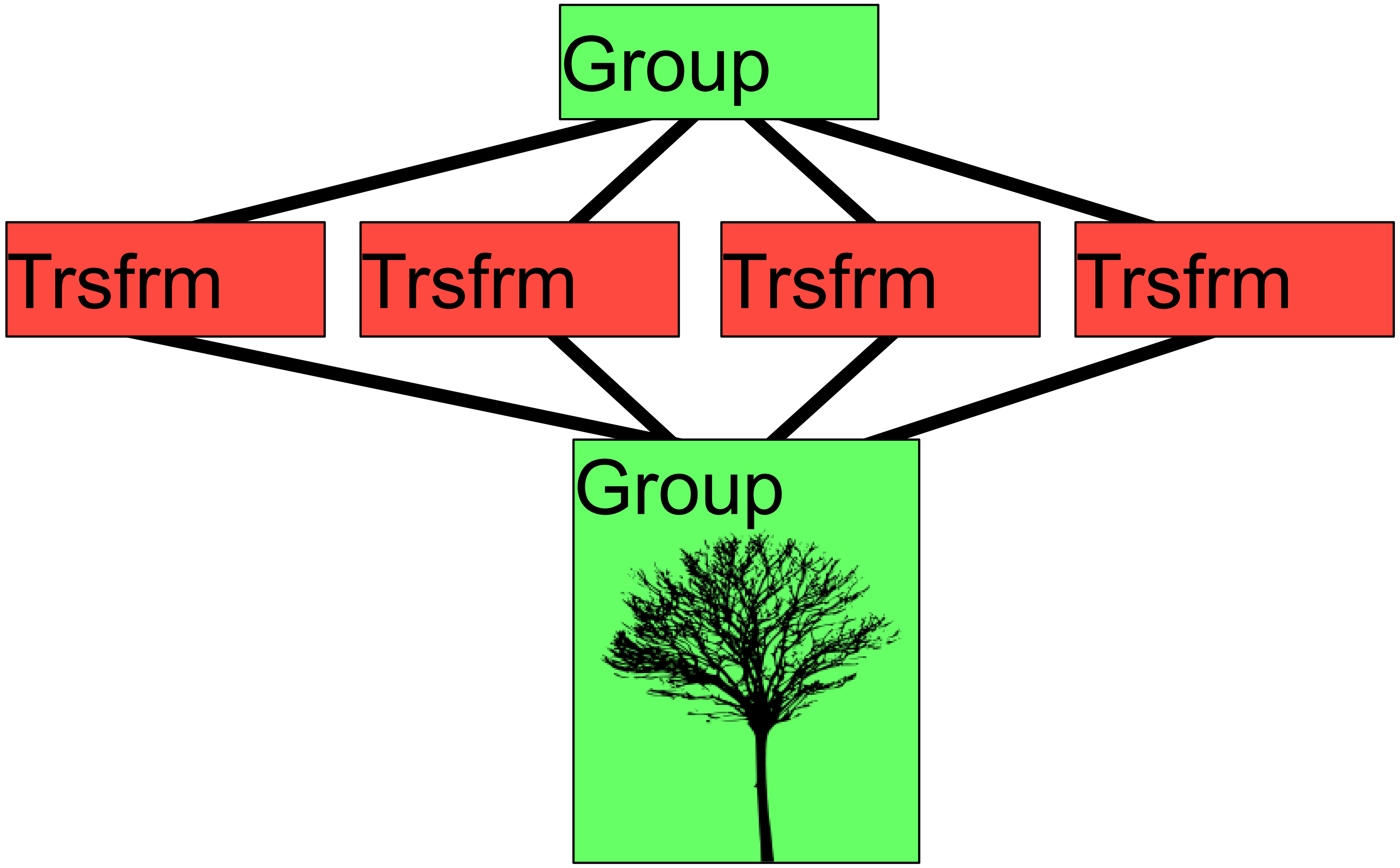
- Basic idea: Tree
- Comprised of several node types
  - Shape: 3D geometric objects
  - Transform: Affect current transformation
  - Property: Color, texture
  - Group: Collection of subgraphs

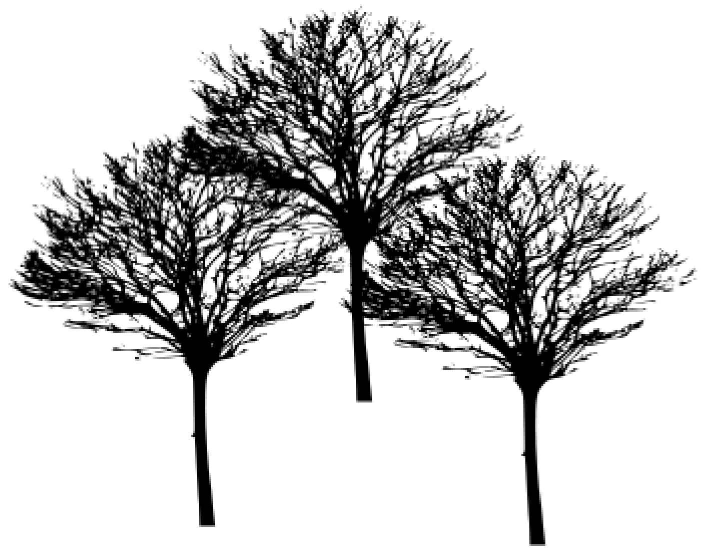


- C++ implementation
  - base class Object
    - children, parent
  - derived classes for each node type (group, transform)

Scene Graph Representation

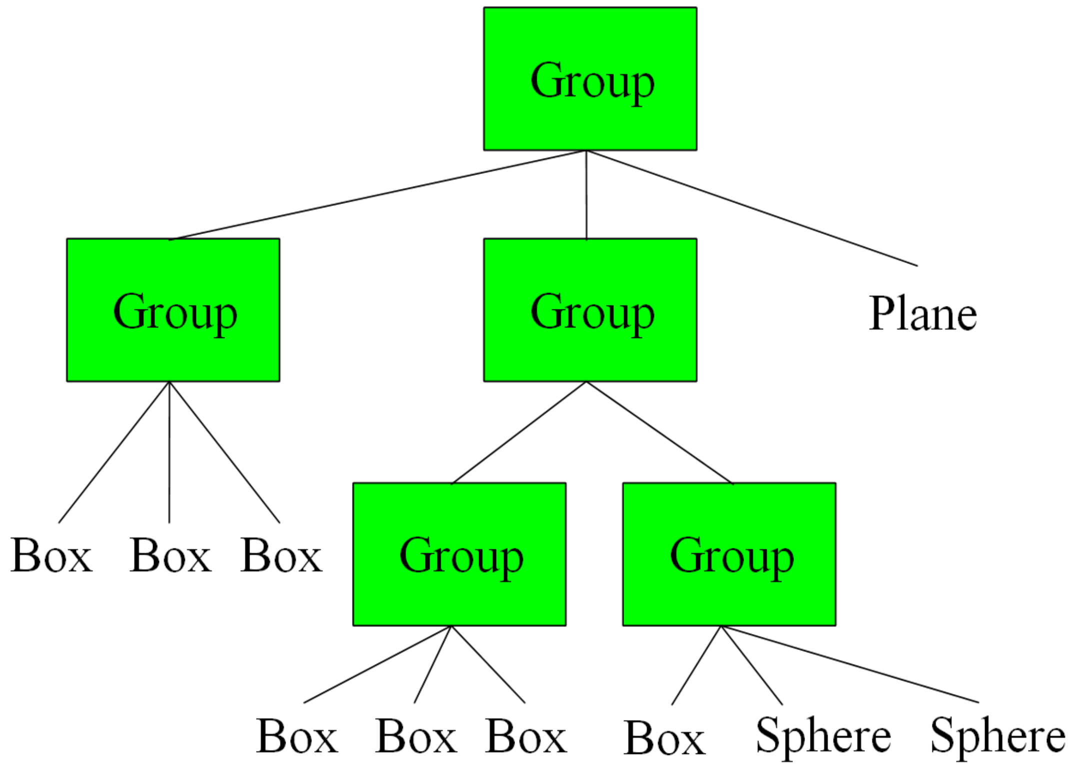
- In fact, generalization of a tree: Directed Acyclic Graph (DAG)
  - Means a node can have multiple parents, but cycles are not allowed
- Why? Allows multiple instantiations
  - Reuse complex hierarchies many times in the scene using different transformations (example: a tree)
    - Of course, if you only want to reuse meshes, just load the mesh once and make several geometry nodes point to the same data

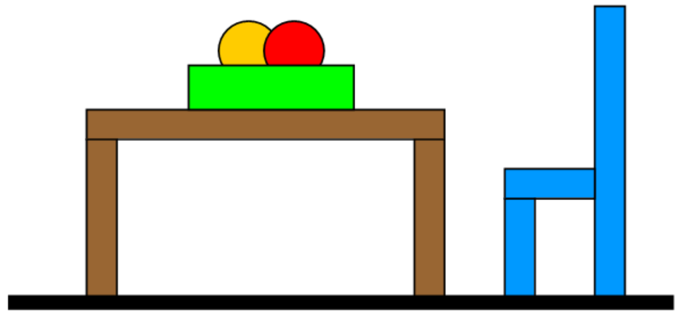




Simple Example with Groups

```
Group {
    numObjects 3
    Group {
        numObjects 3
        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> } }
    Group {
        numObjects 2
        Group {
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> } }
        Group {
            Box { <BOX PARAMS> }
            Sphere { <SPHERE PARAMS> }
            Sphere { <SPHERE PARAMS> } } }
    Plane { <PLANE PARAMS> } }
```





Text format is fictitious, better to use XML in real applications

Simple Example with Groups

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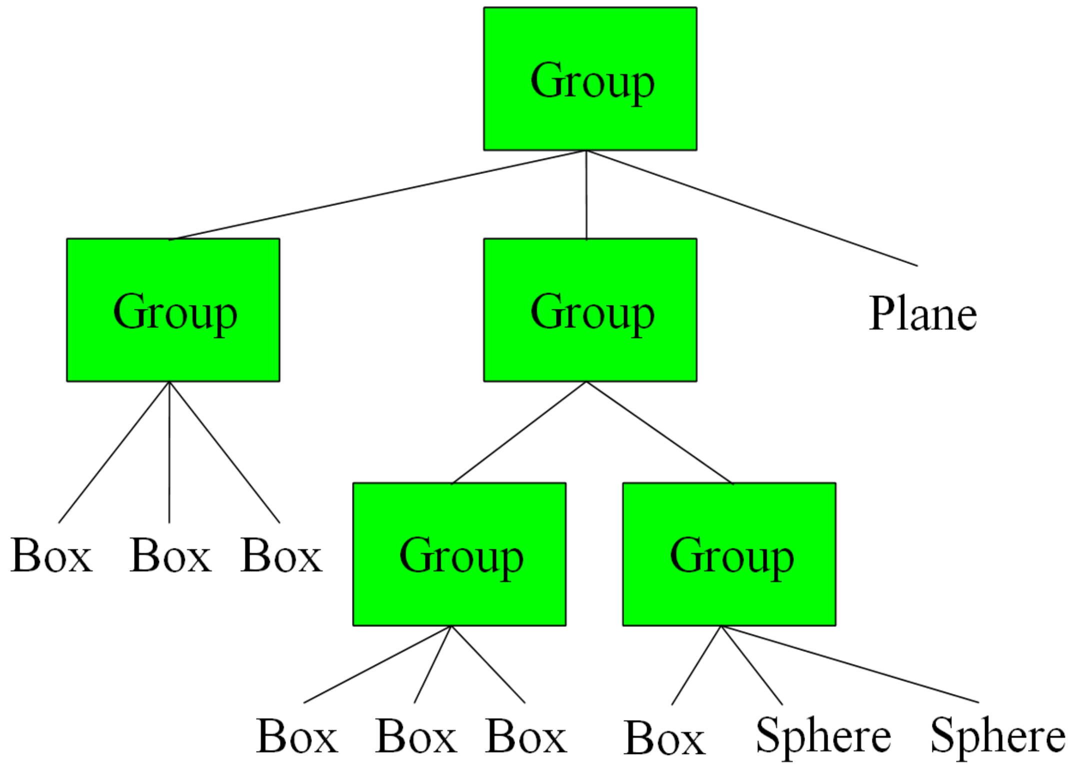
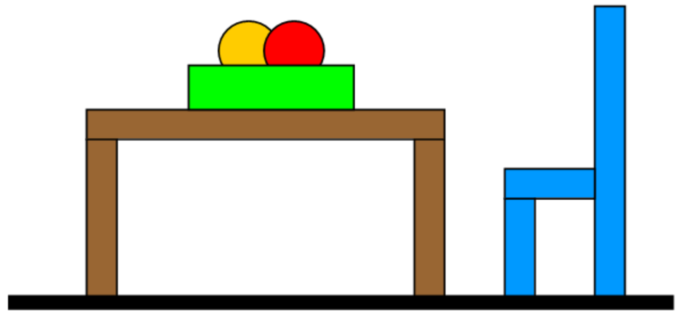
Group {
    numObjects 3
    Group {
        numObjects 3
        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> } }
    Group {
        numObjects 2
        Group {
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> } }
        Group {
            Box { <BOX PARAMS> }
            Sphere { <SPHERE PARAMS> }
            Sphere { <SPHERE PARAMS> } } }
    Plane { <PLANE PARAMS> } }
```





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    numObjects 3
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        numObjects 3
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        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> } }
    Group {
        numObjects 2
        Group {
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> } }
        Group {
            Box { <BOX PARAMS> }
            Sphere { <SPHERE PARAMS> }
            Sphere { <SPHERE PARAMS> } } }
    Plane { <PLANE PARAMS> } }
```
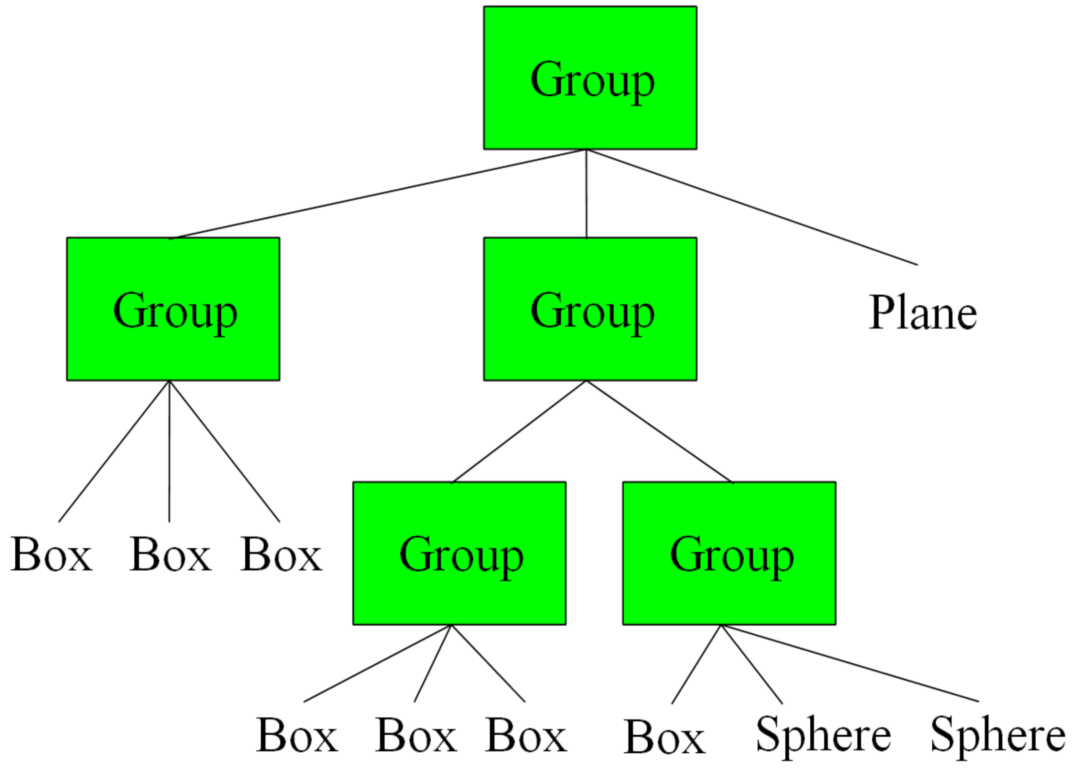
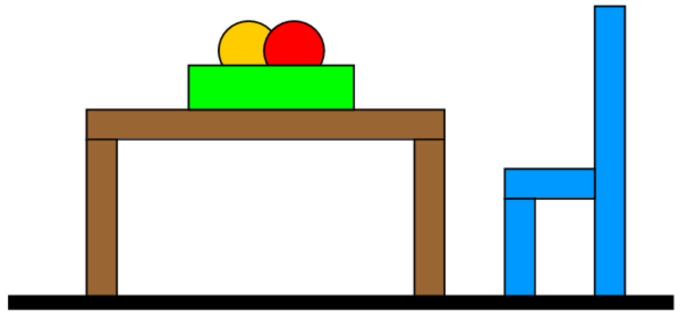
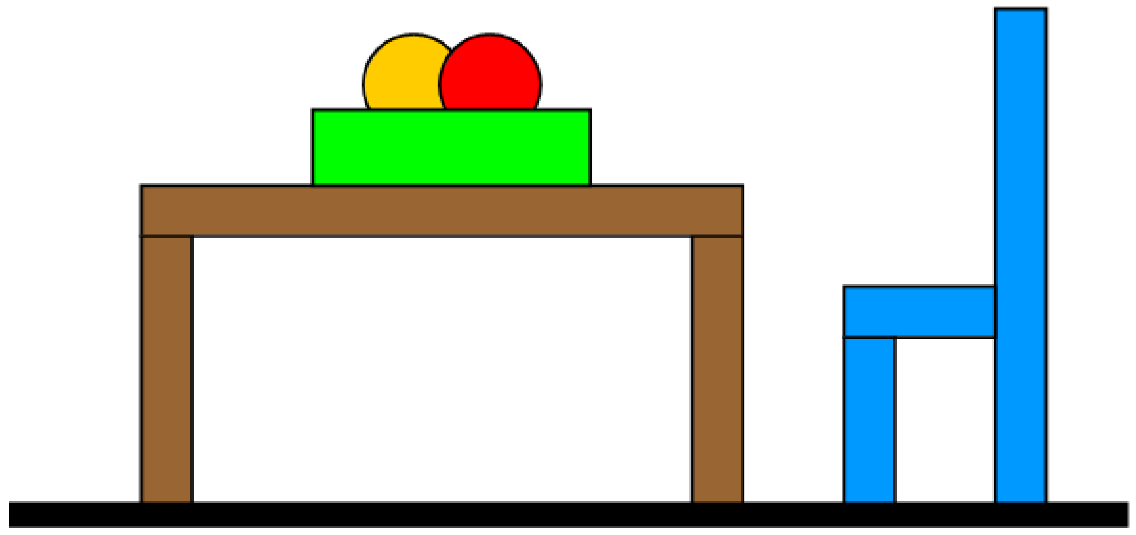





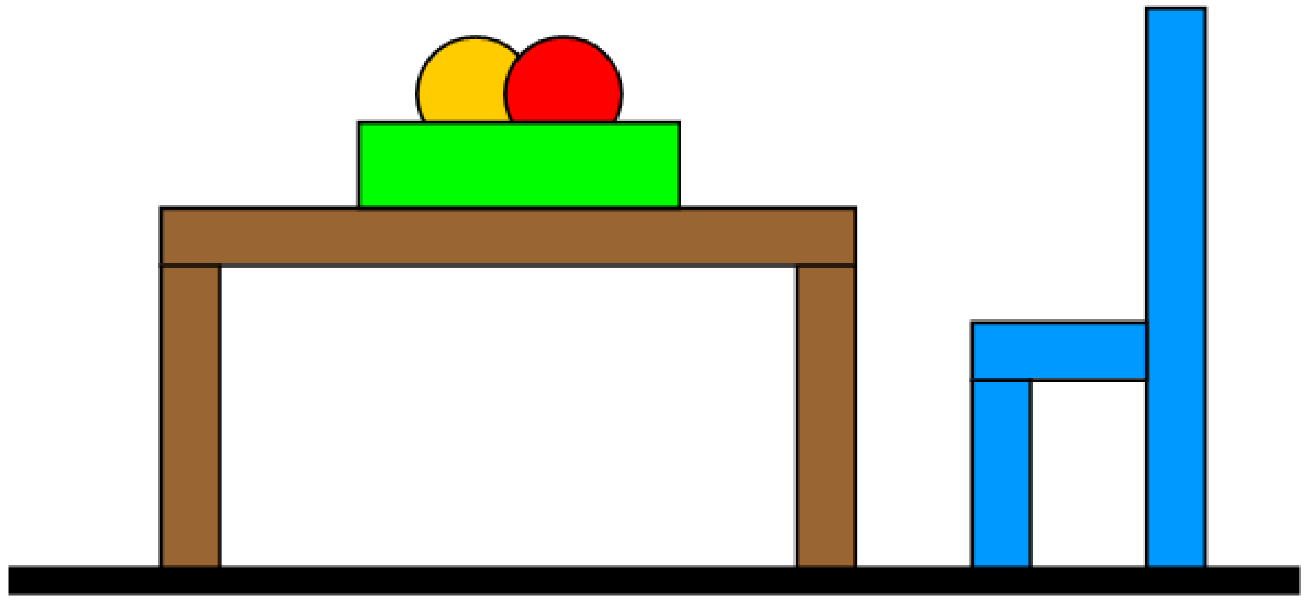
Here we have only simple shapes, but easy to add a “Mesh” node whose parameters specify an .OBJ to load (say)

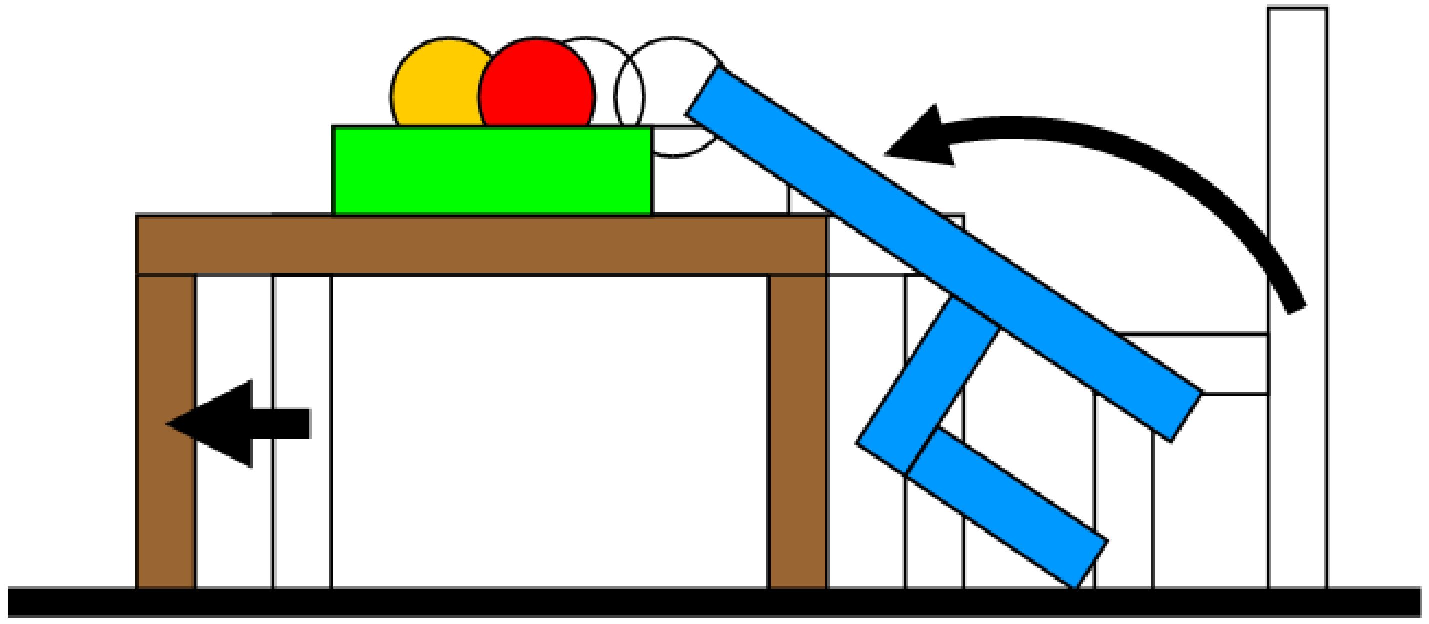
Adding Attributes (Material, etc.)

```
Group {
    numObjects 3
    Material { <BLUE> }
    Group {
        numObjects 3
        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> }
        Box { <BOX PARAMS> } }
    Group {
        numObjects 2
        Material { <BROWN> }
        Group {
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> }
            Box { <BOX PARAMS> } }
        Group {
            Material { <GREEN> }
            Box { <BOX PARAMS> }
            Material { <RED> }
            Sphere { <SPHERE PARAMS> }
            Material { <ORANGE> }
            Sphere { <SPHERE PARAMS> } } }

    Plane { <PLANE PARAMS> } }
```



Adding Transformations



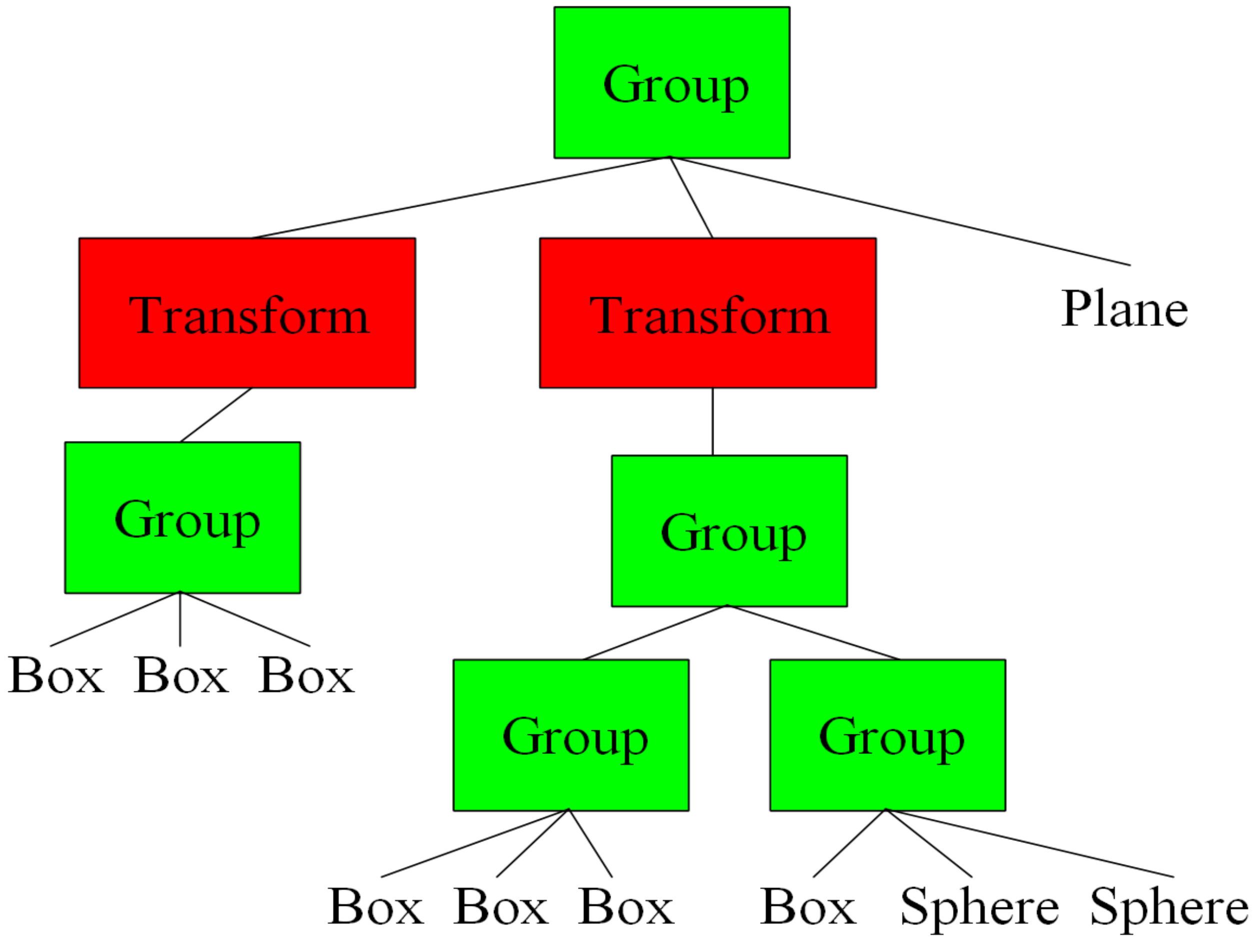


Questions?

Scene Graph Traversal

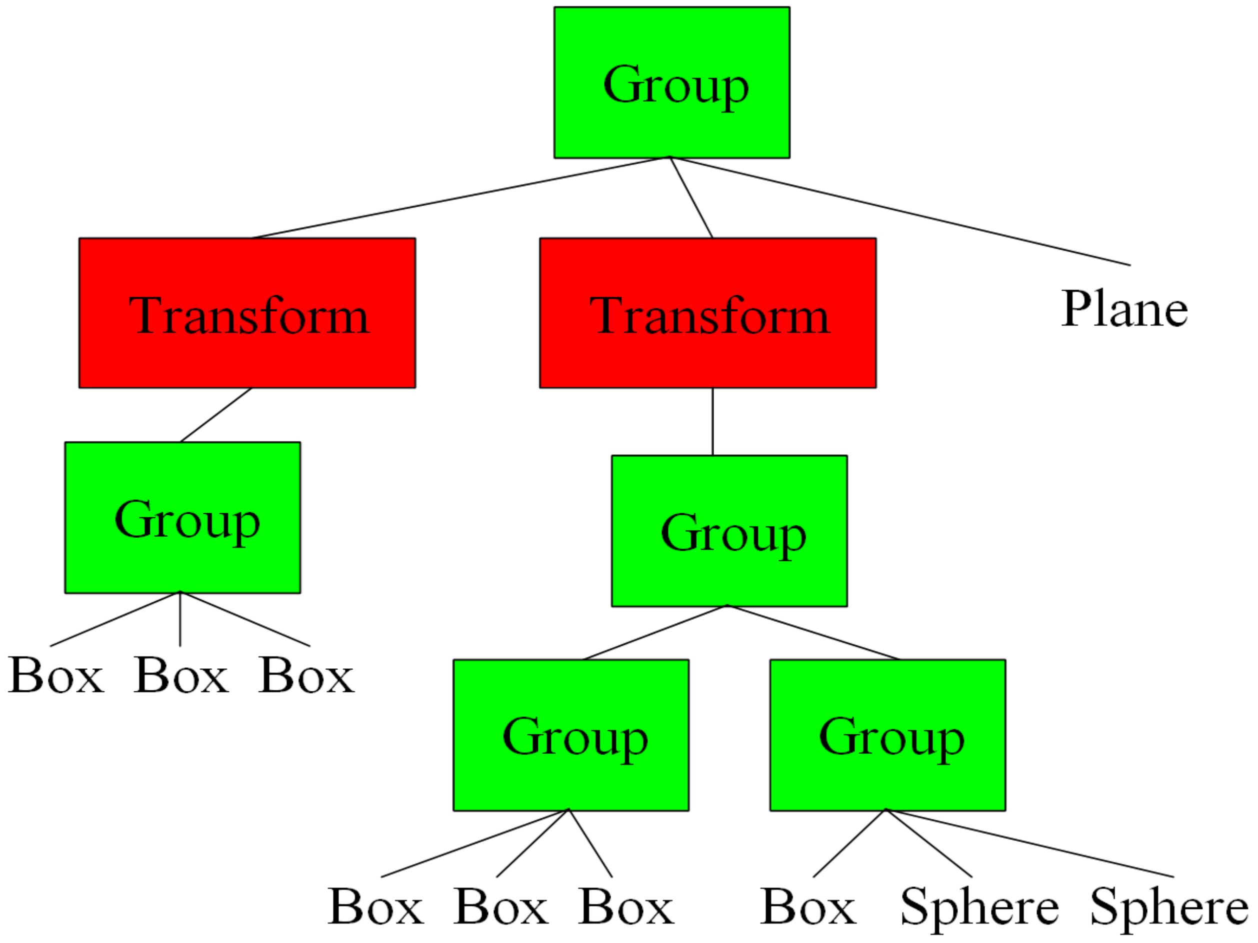
- Depth first recursion
  - Visit node, then visit subtrees (top to bottom, left to right)
  - When visiting a geometry node: Draw it!

- How to handle transformations?
  - Remember, transformations are always specified in coordinate system of the parent



Scene Graph Traversal

- How to handle transformations?
  - Traversal algorithm keeps a **transformation state S** (a 4x4 matrix)
    - from world coordinates
    - Initialized to identity in the beginning
  - Geometry nodes always drawn using current **S**
  - When visiting a transformation node **T**: multiply current state **S** with **T**, then visit child nodes
    - Has the effect that nodes below will have new transformation
  - When all children have been visited, **undo the effect of T!**



Recall frames

- An object frame has coordinates O in the world
  (of course O is also our 4x4 matrix)

$$\vec{\mathbf{o}}^t = \vec{\mathbf{w}}^t O$$

- Then we are given coordinates c in the object frame

$$\vec{\mathbf{o}}^t \mathbf{c} = \vec{\mathbf{w}}^t O \mathbf{c}$$

- Indeed we need to apply matrix O to all objects

Frames and hierarchy

- Matrix *M1* to go from world to torso $\vec{\mathbf{t}}^t = \vec{\mathbf{w}}^t M_1$
- Matrix *M2* to go from torso to arm $\vec{\mathbf{a}}^t = \vec{\mathbf{t}}^t M_2$

- How do you go from arm coordinates to world?

$$\vec{\mathbf{a}}^t \mathbf{c} = \vec{\mathbf{t}}^t M_2 \mathbf{c} = \vec{\mathbf{w}}^t M_1 M_2 \mathbf{c}$$

- We can concatenate the matrices
- Matrices for the lower hierarchy nodes go to the right

Recap: Scene Graph Traversal

- How to handle transformations?
  - Traversal algorithm keeps a **transformation state S** (a 4x4 matrix)
    - from world coordinates
    - Initialized to identity in the beginning
  - Geometry nodes always drawn using current **S**
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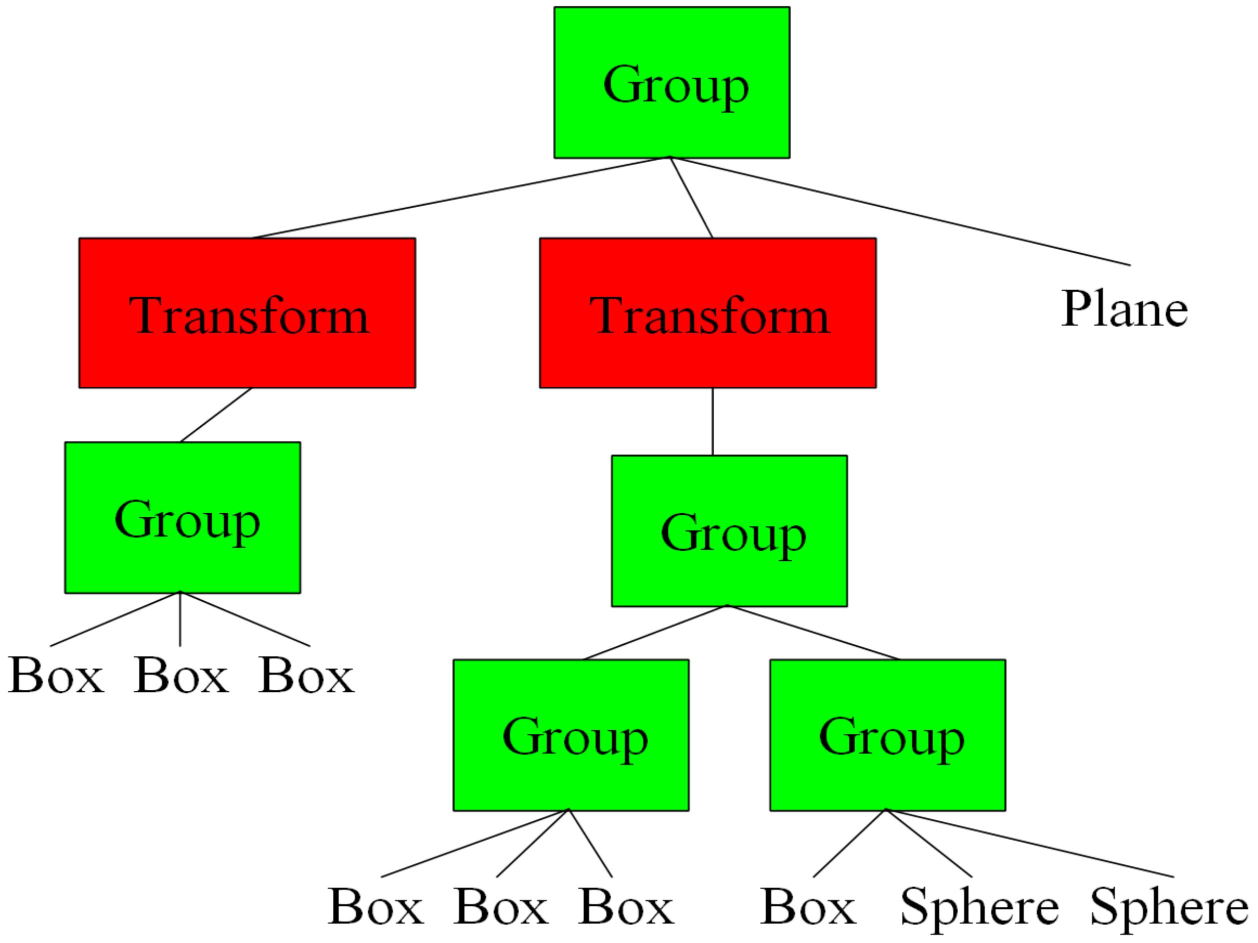
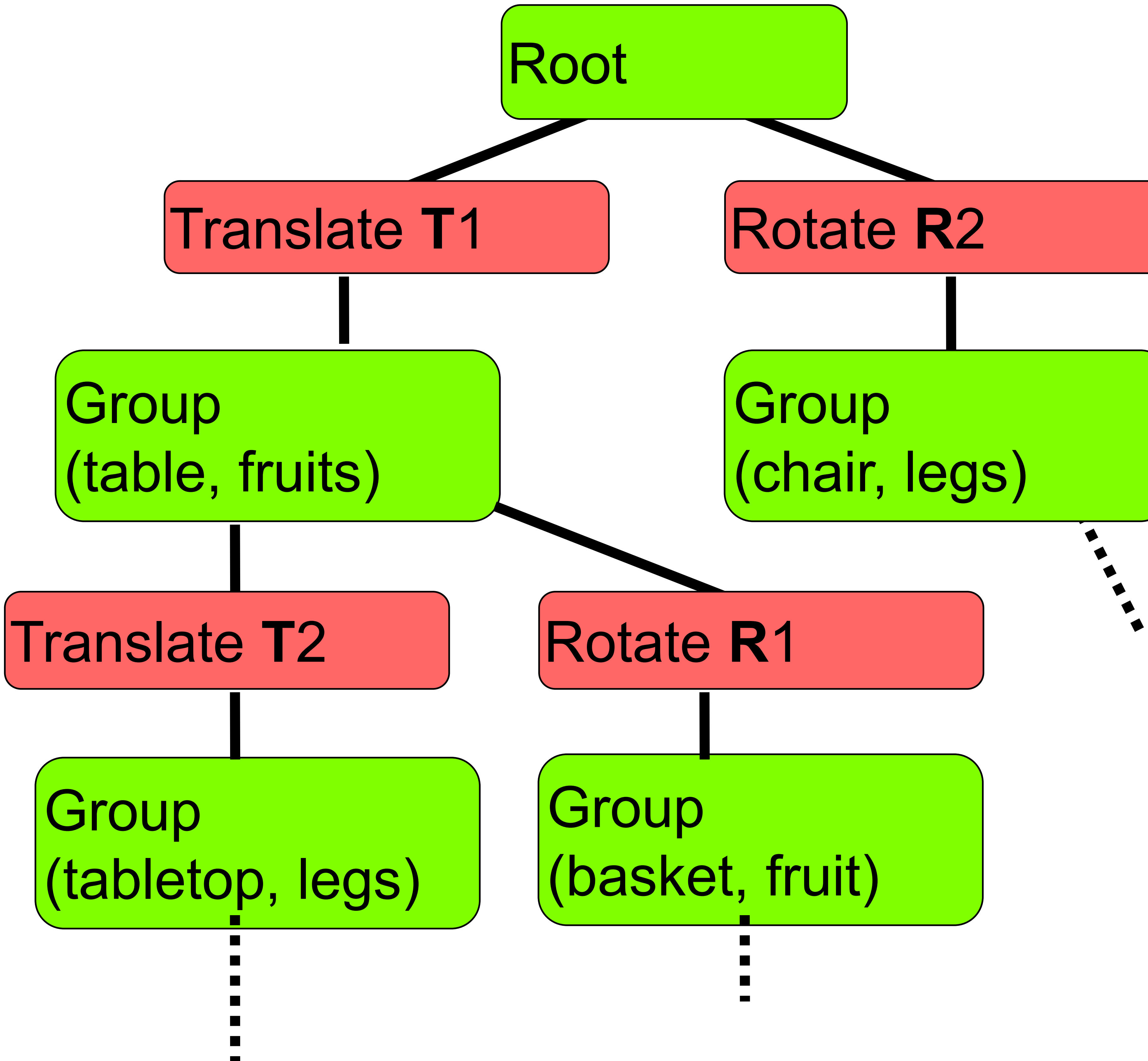
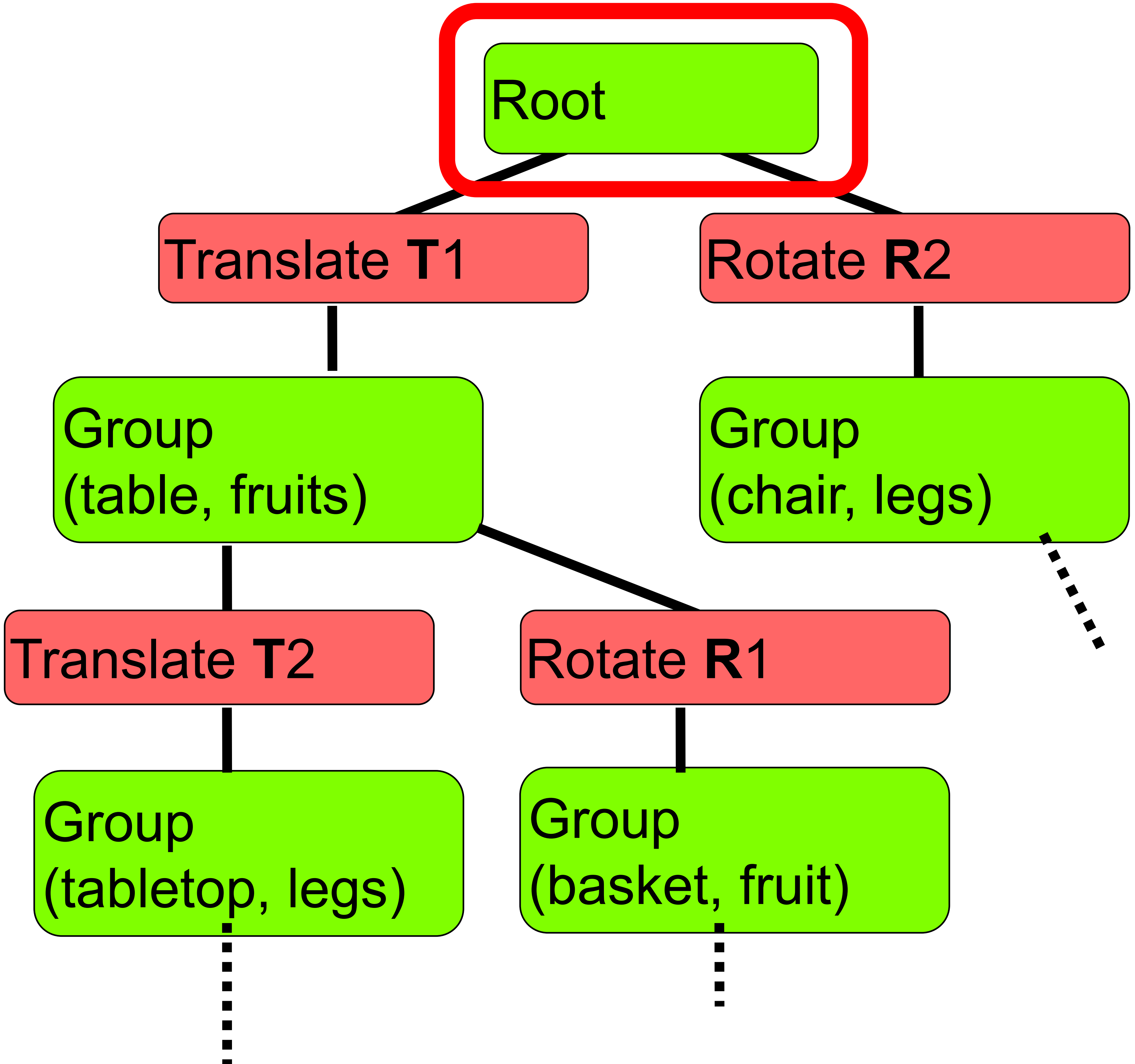


Traversal Example

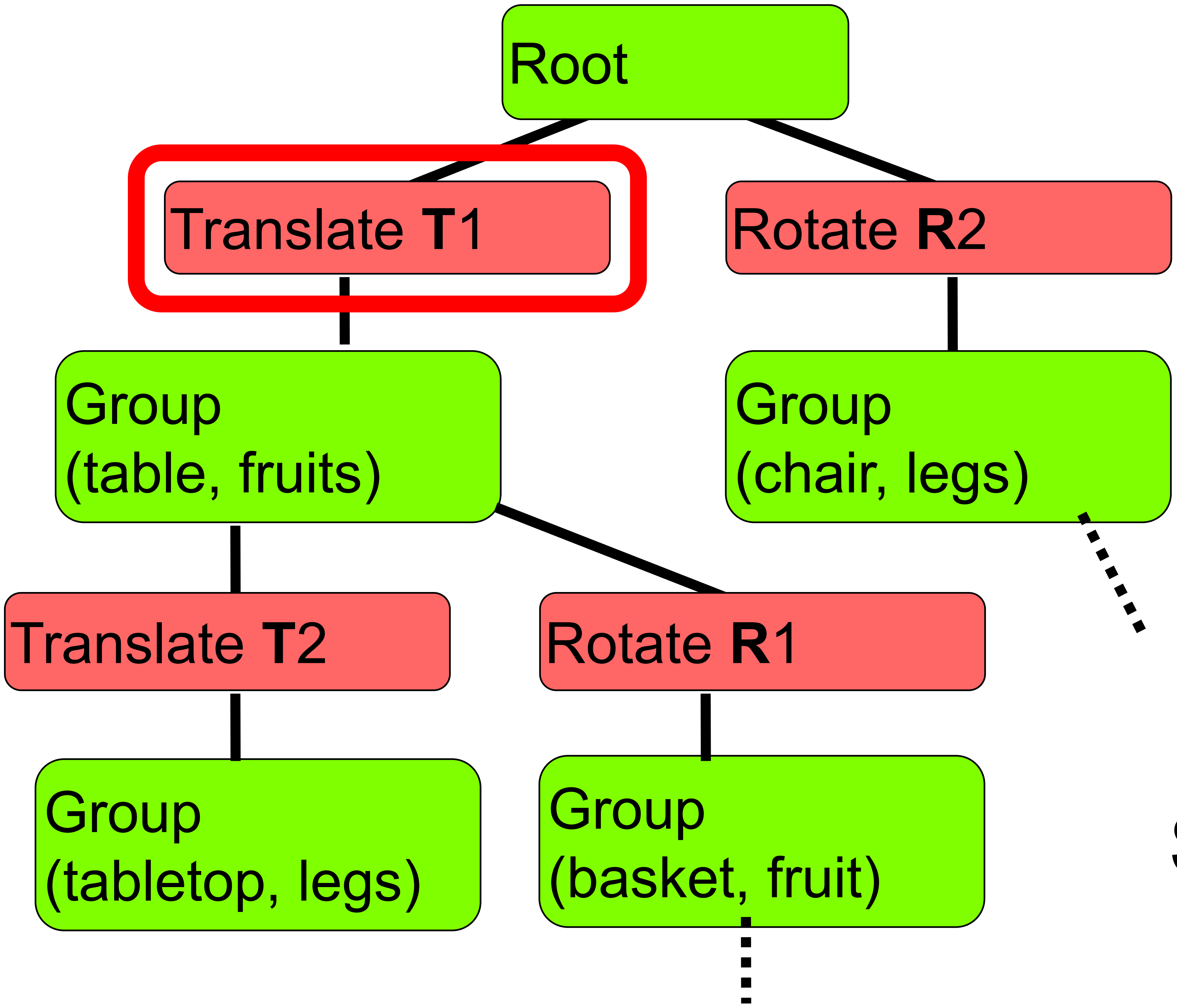


Traversal Example



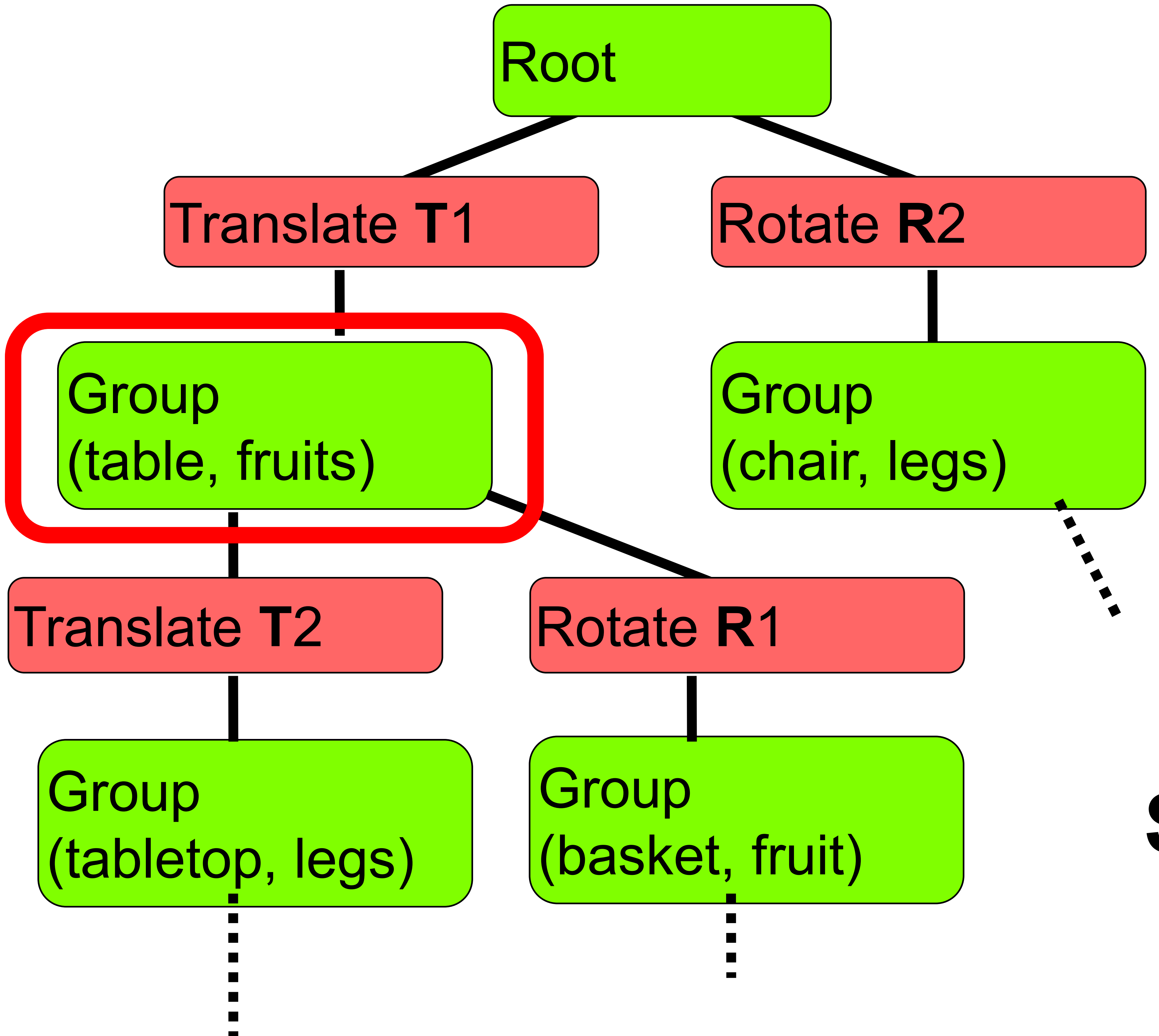
$\mathbf{S} = \mathbf{I}$

Traversal Example



S = **T1**

Traversal Example



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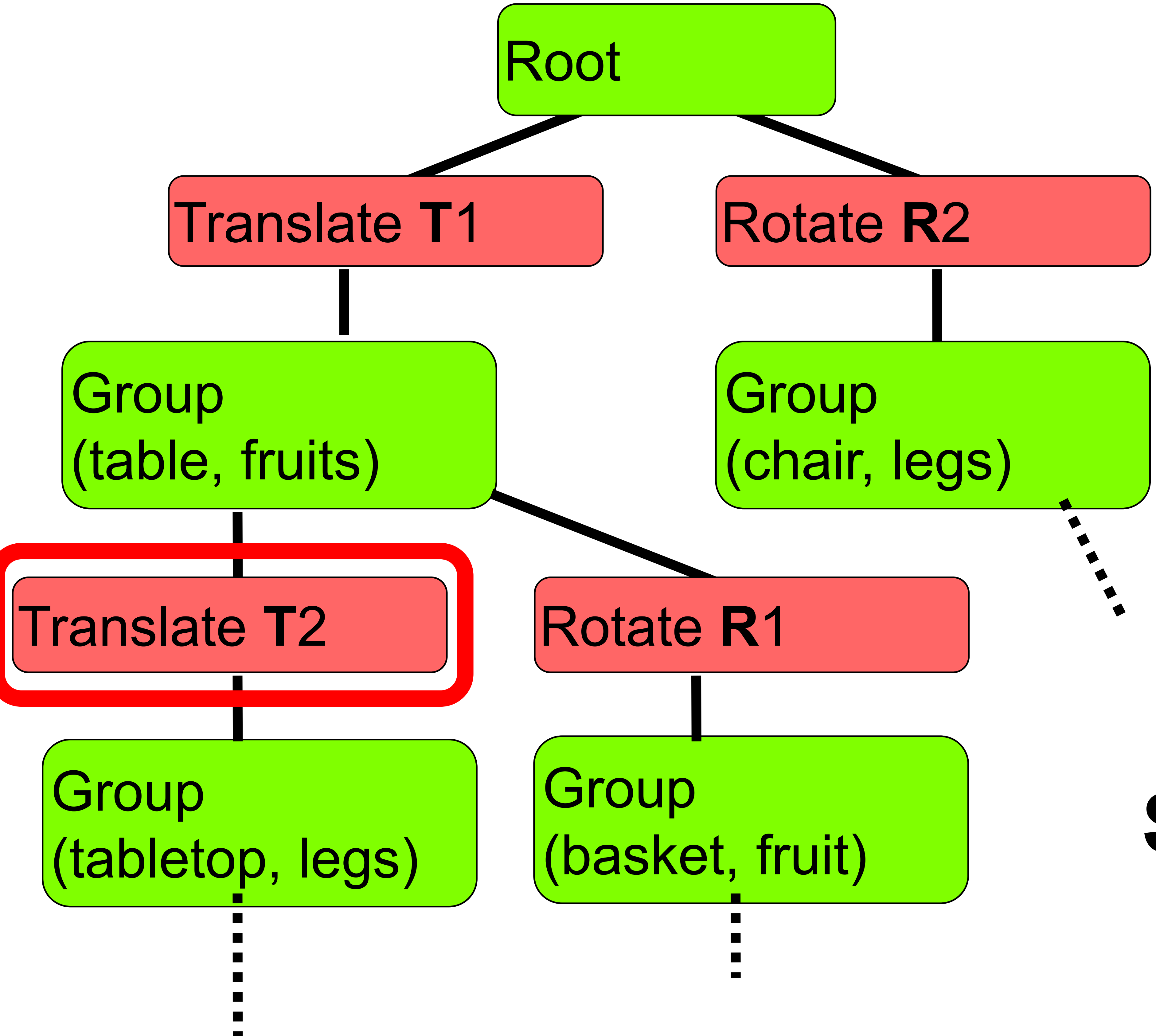
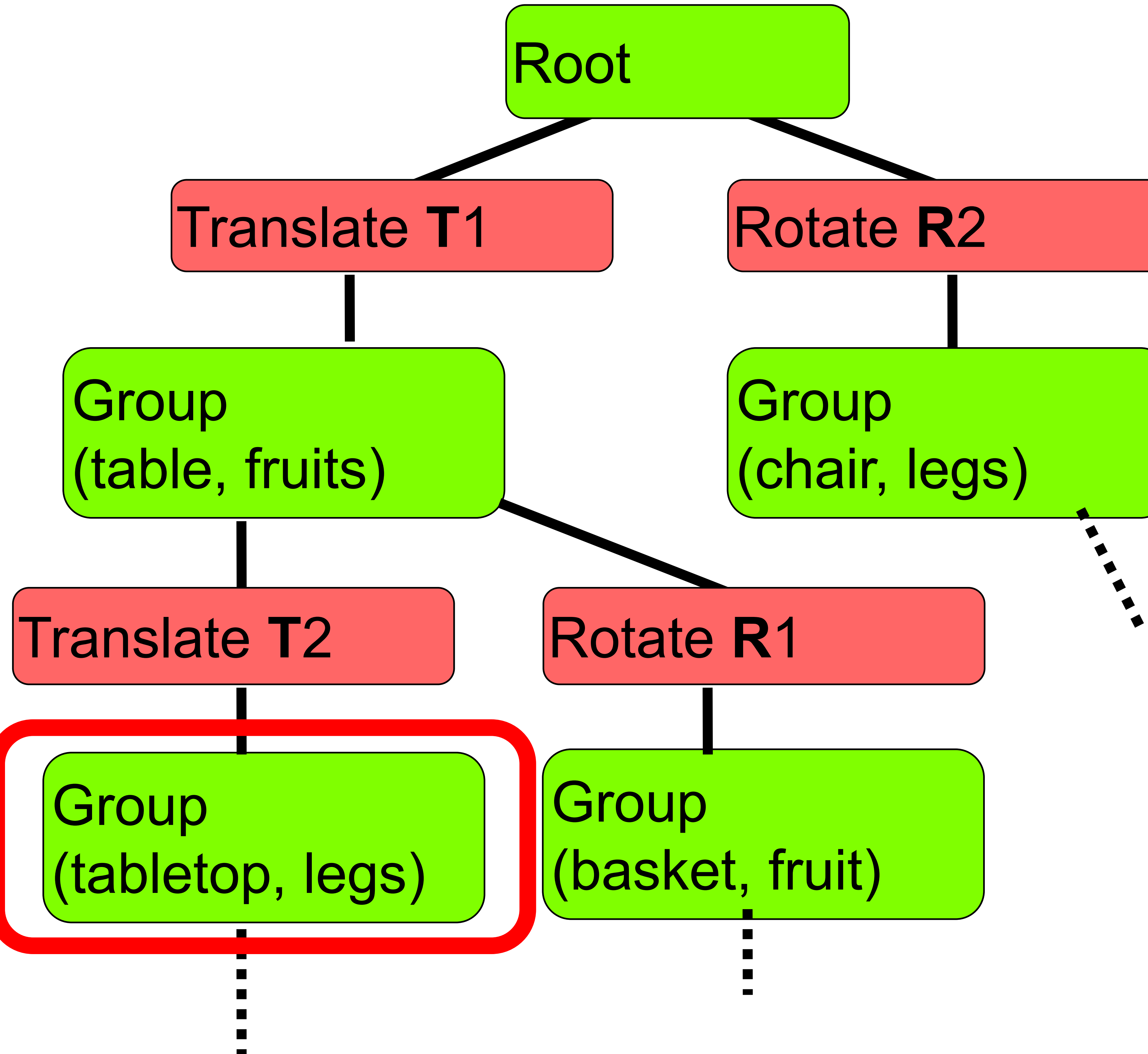
Traversal Example



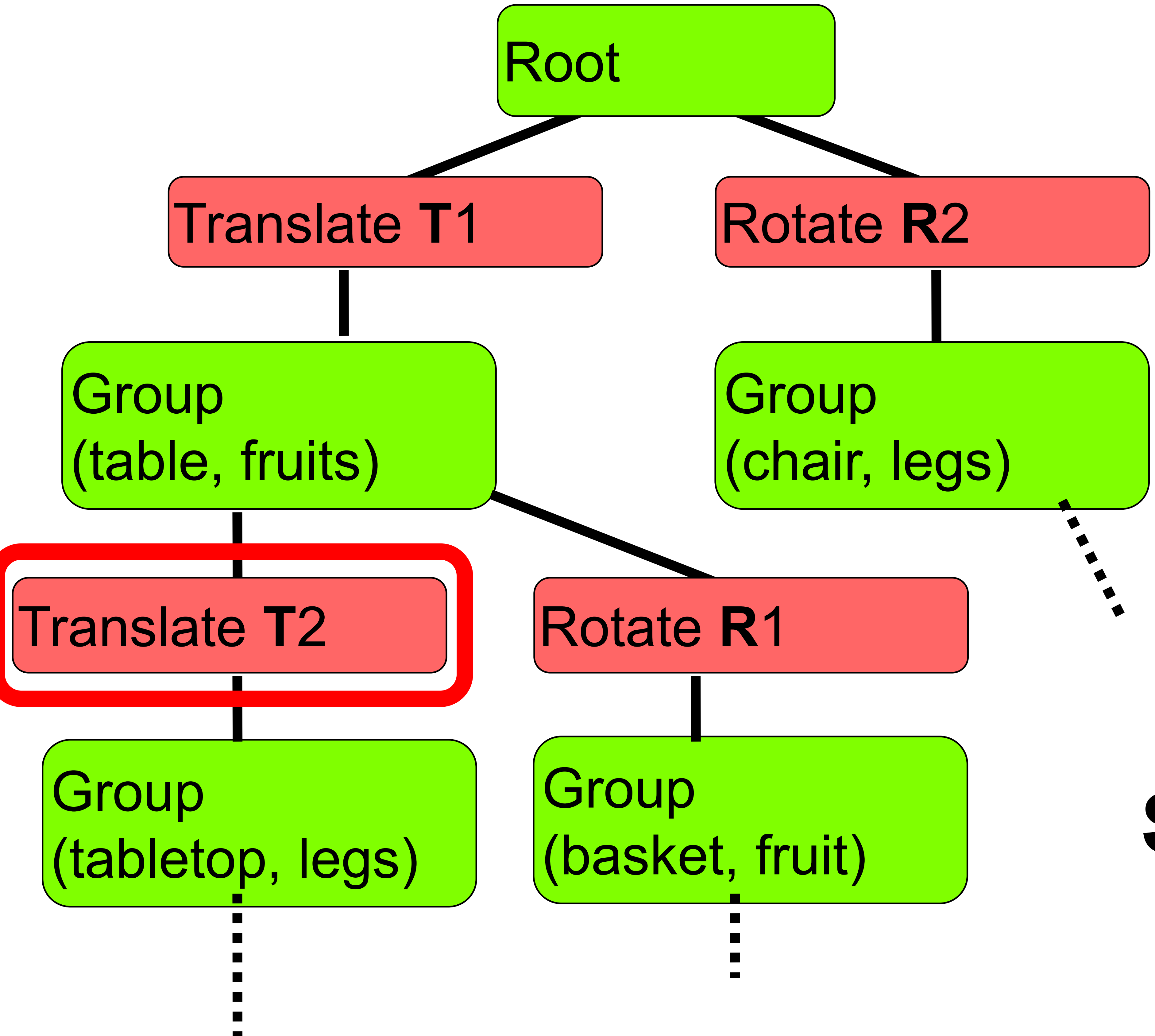
S = **T1 T2**

Traversal Example



S = T1 T2

Traversal Example



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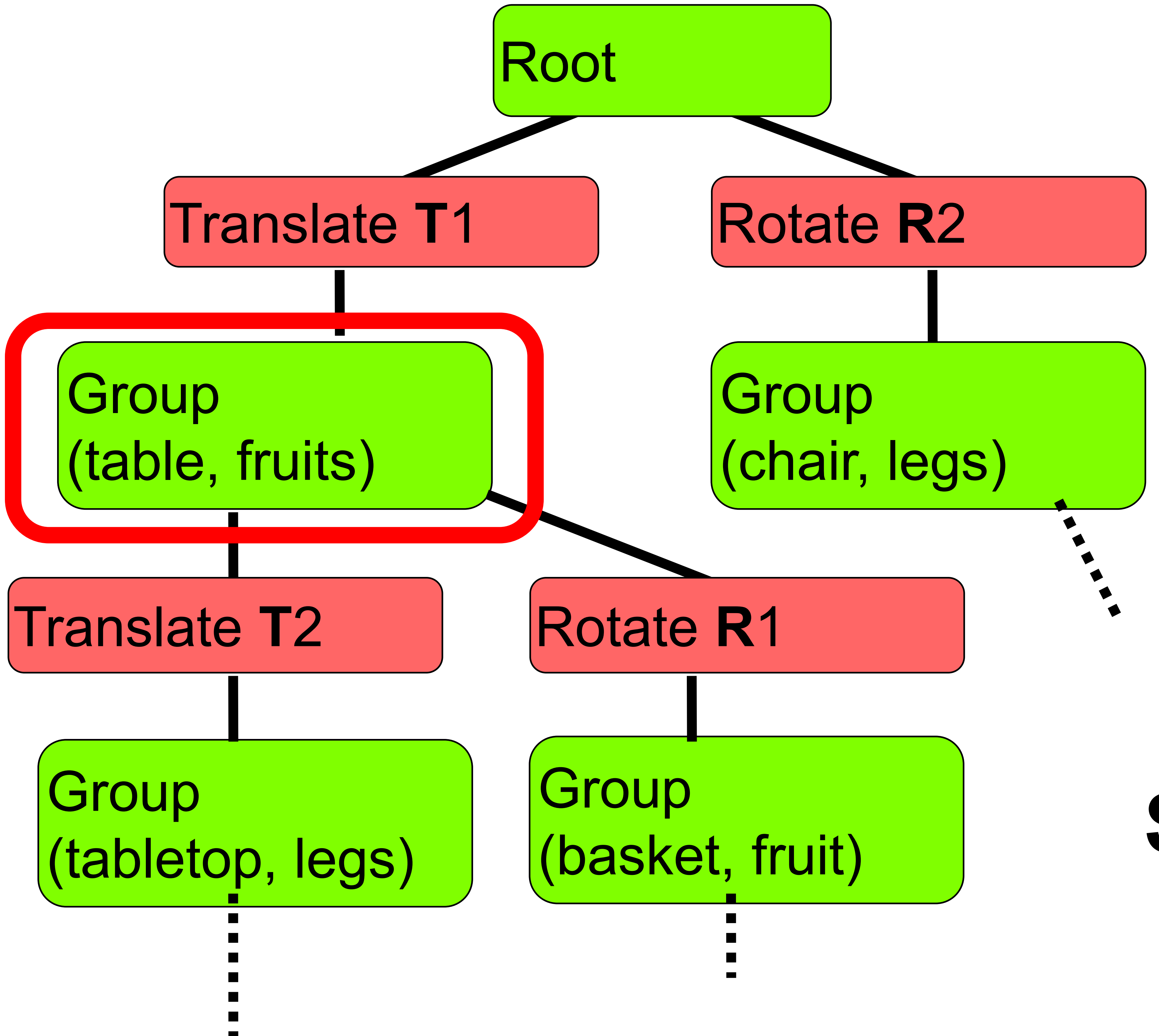
Traversal Example



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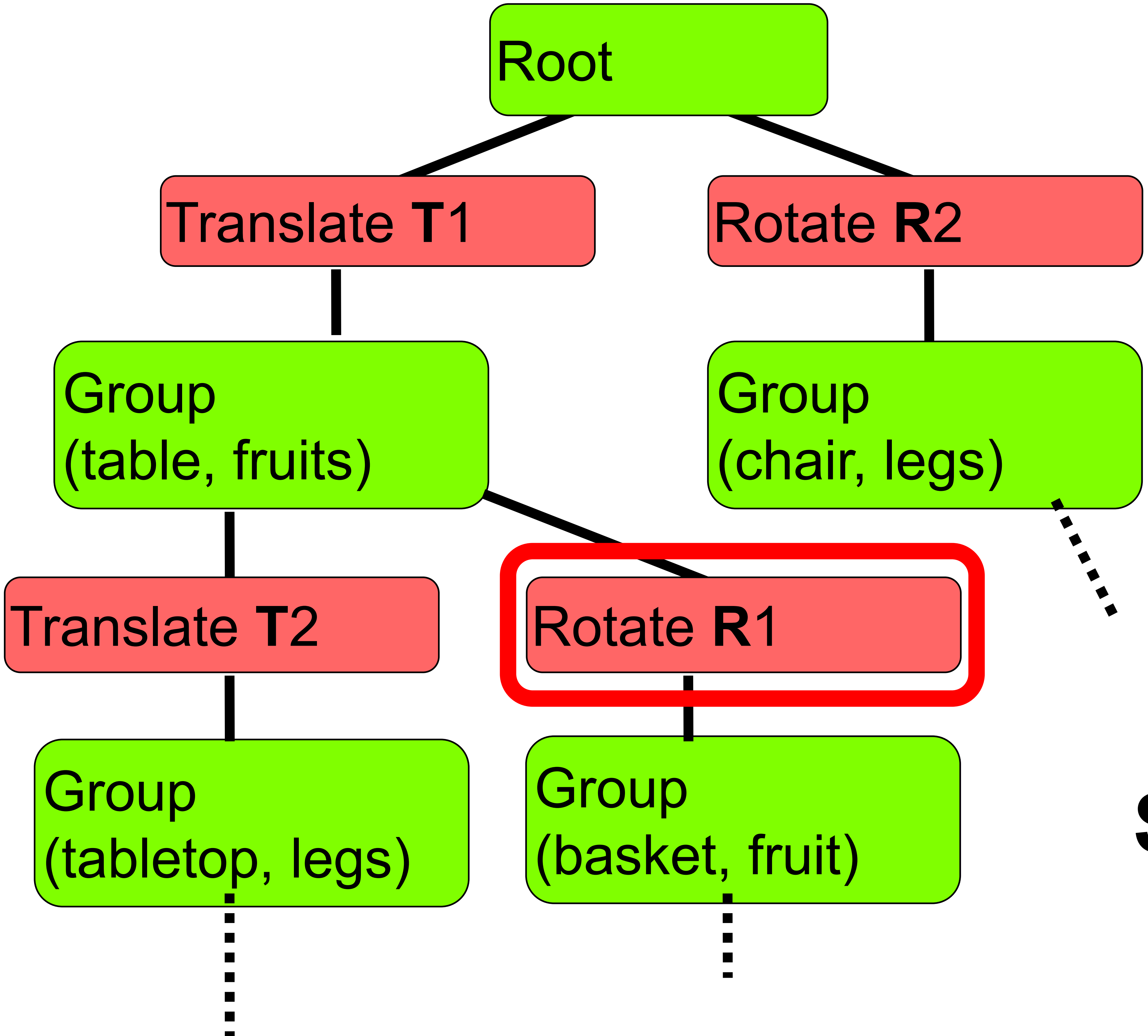
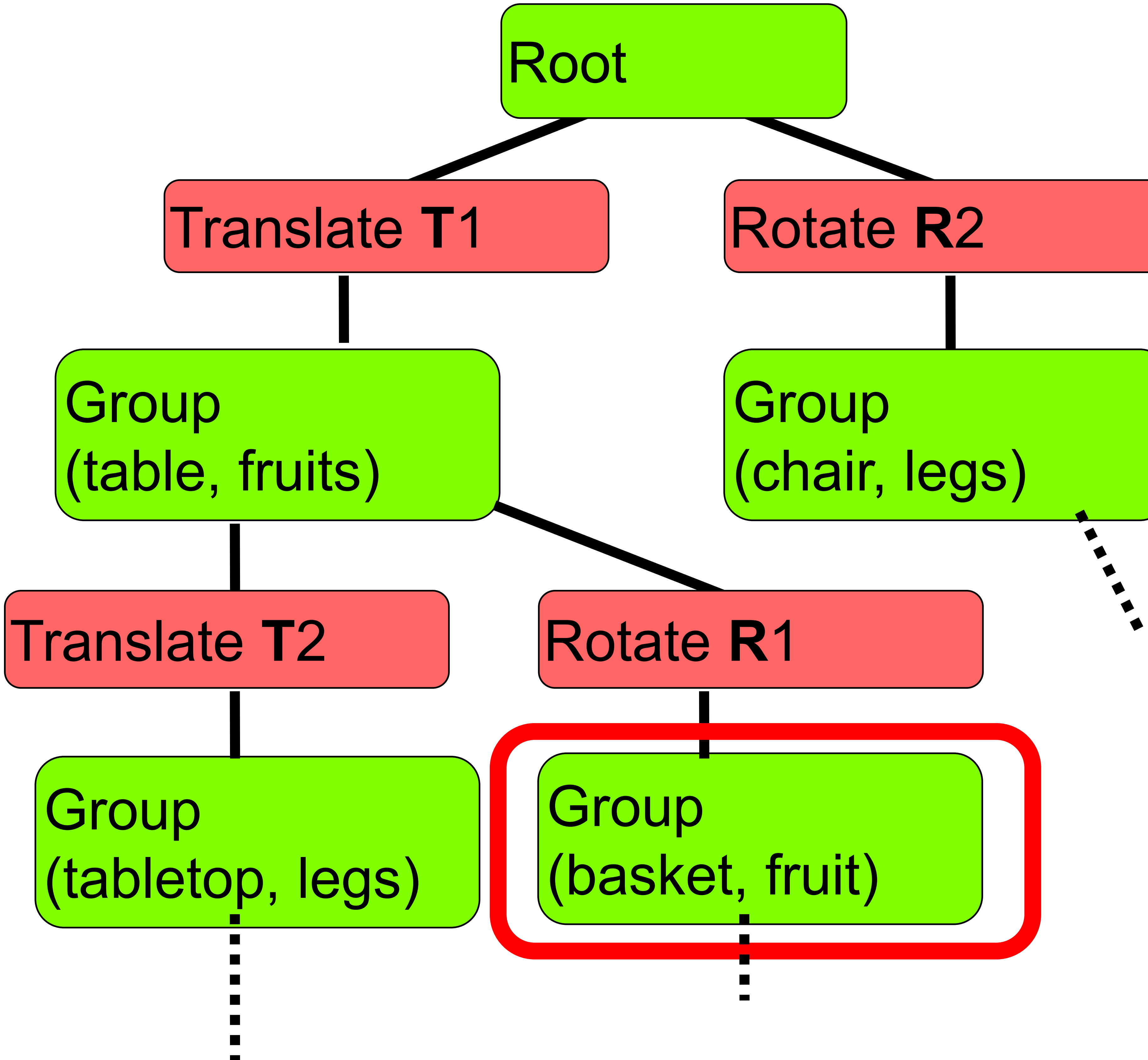
Traversal Example



S = T1 R1

Traversal Example



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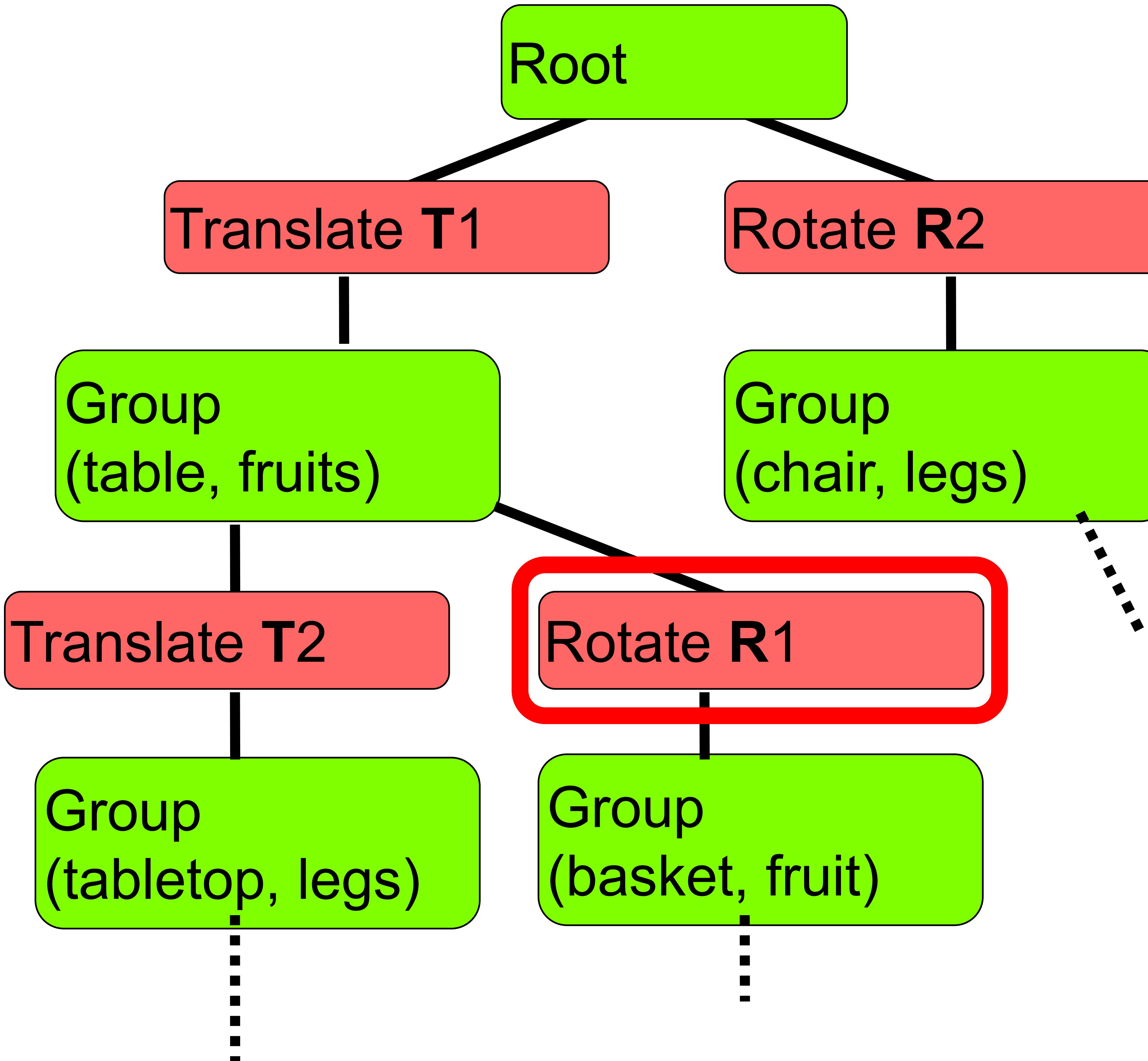
Traversal Example



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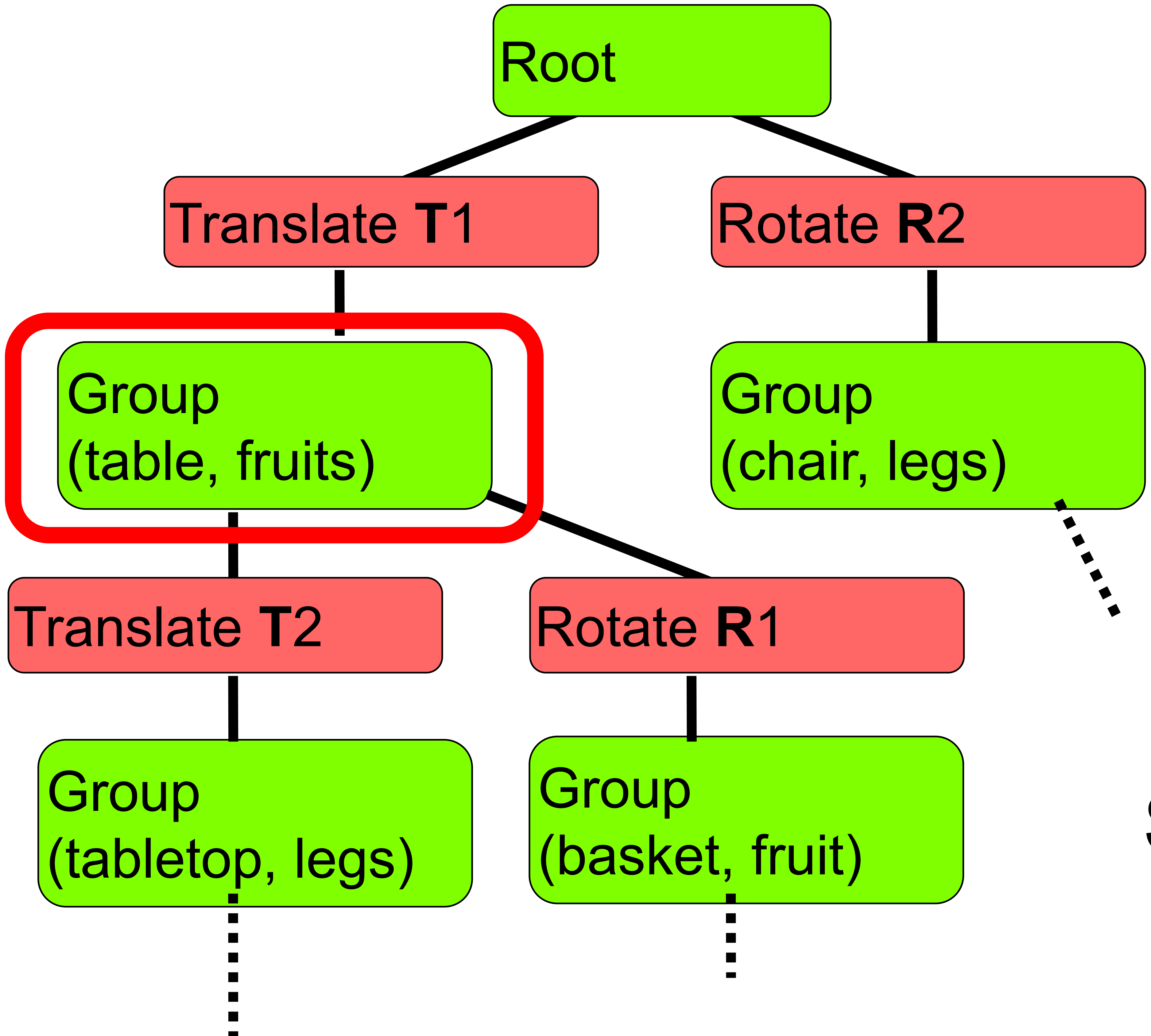

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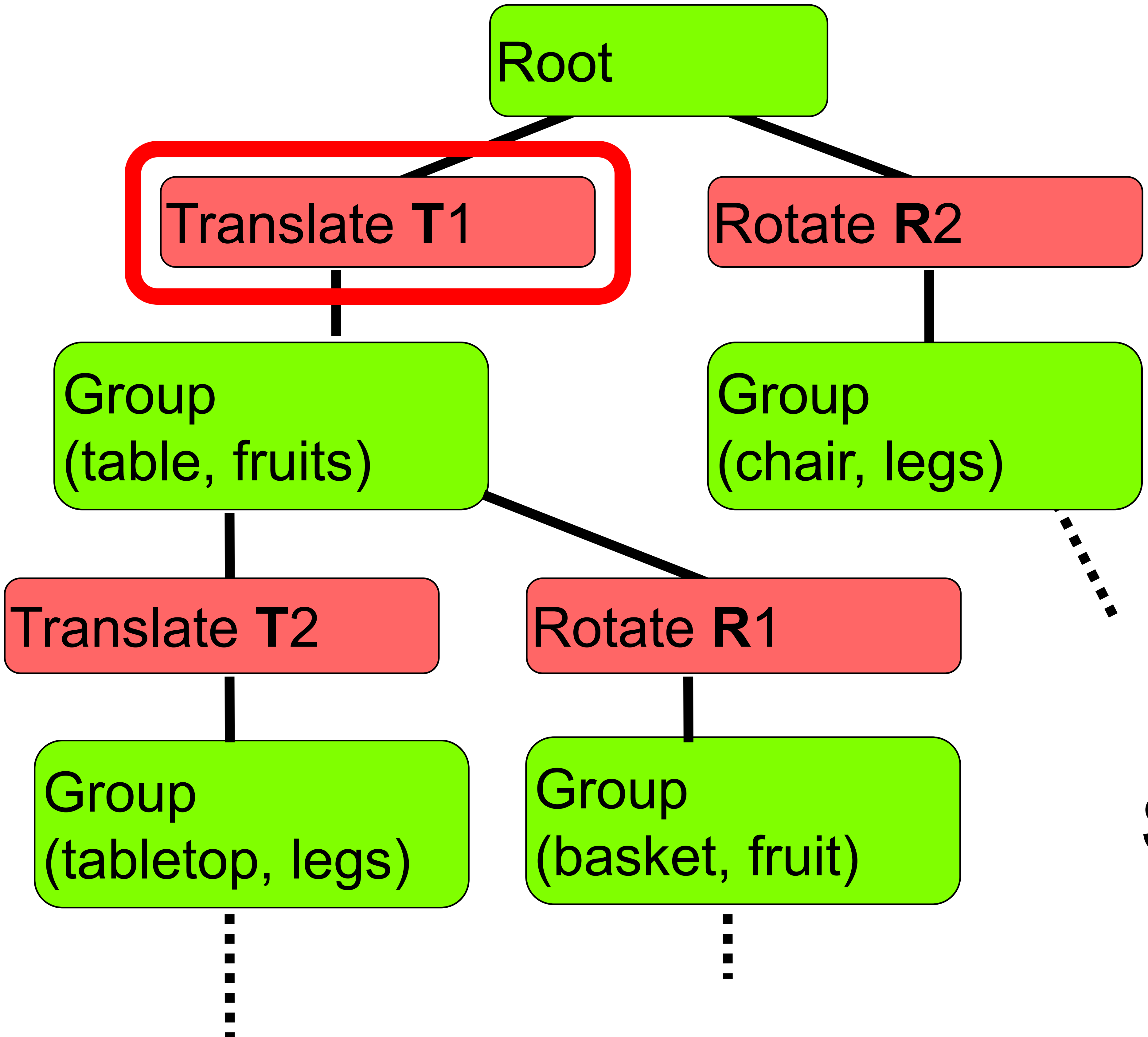
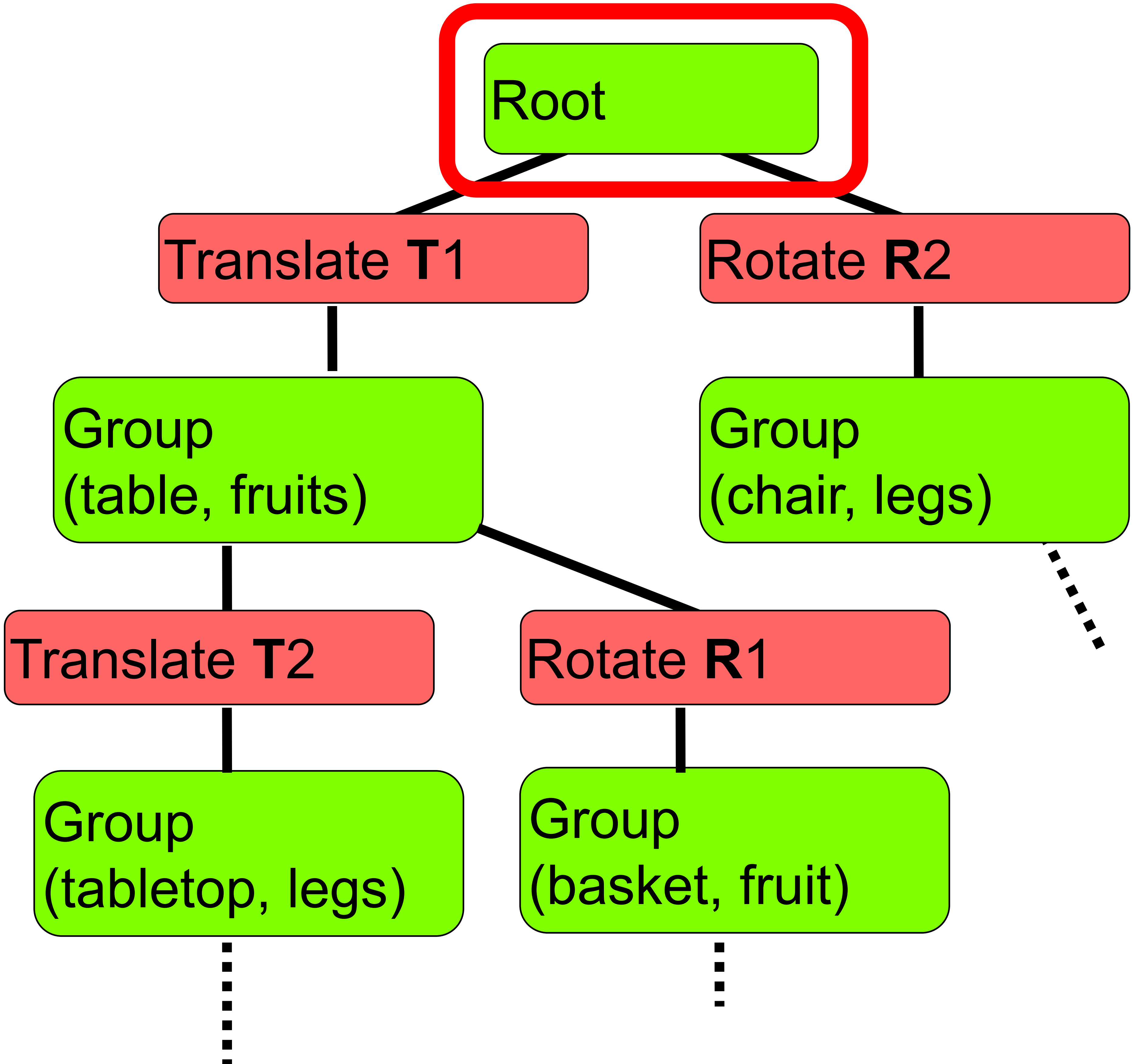


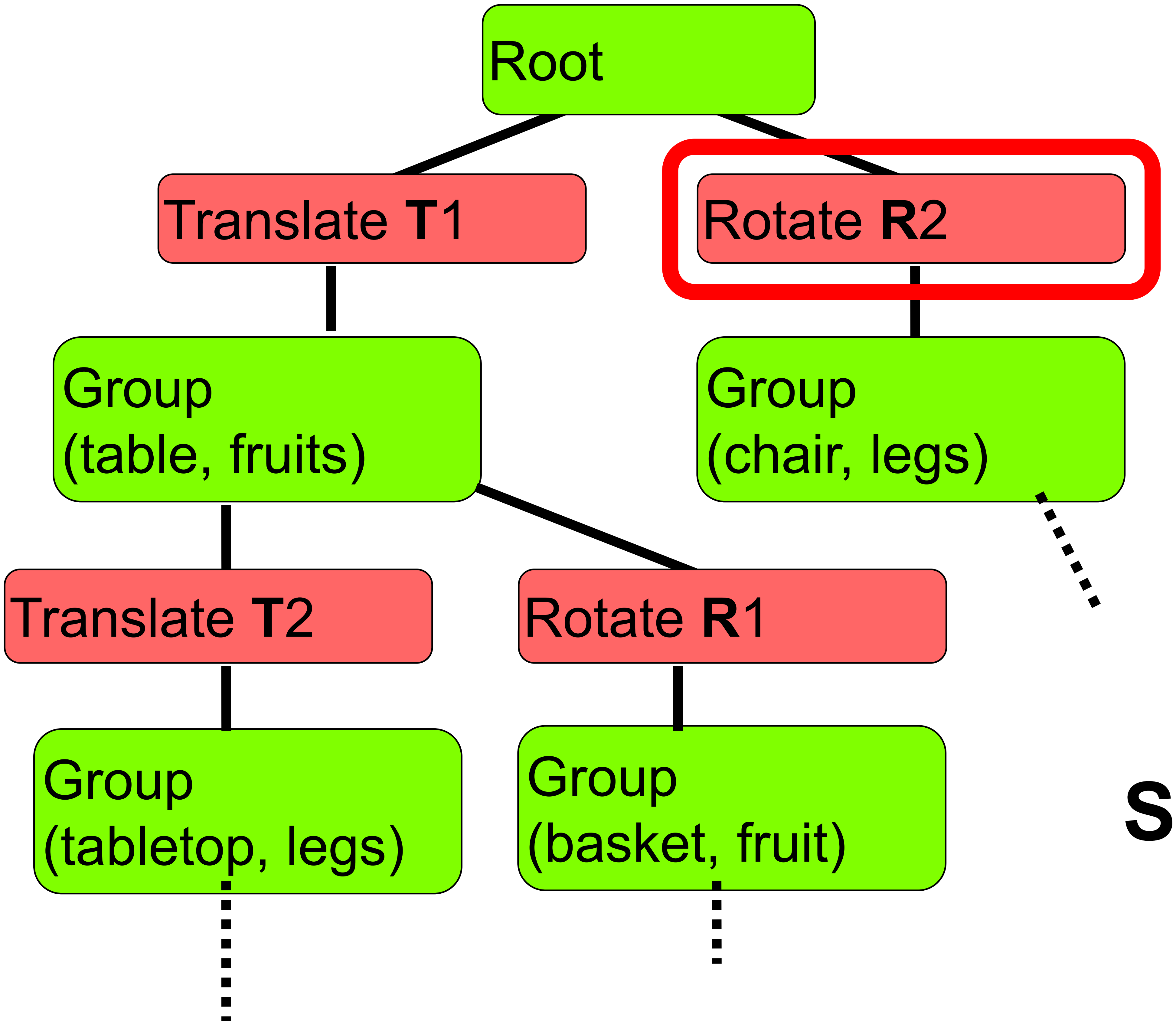
S = **T1**

Traversal Example



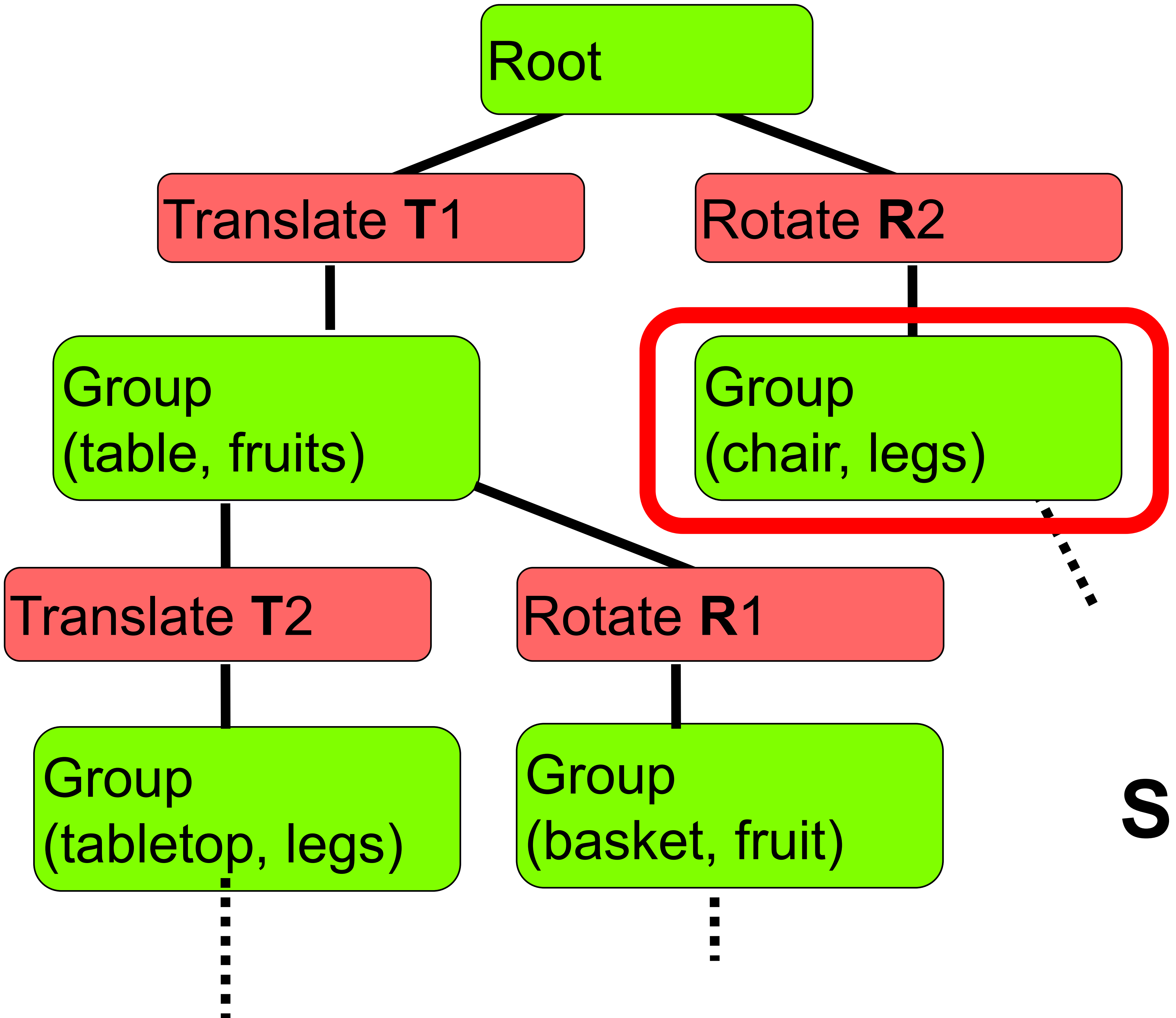
S = **I**

Traversal Example



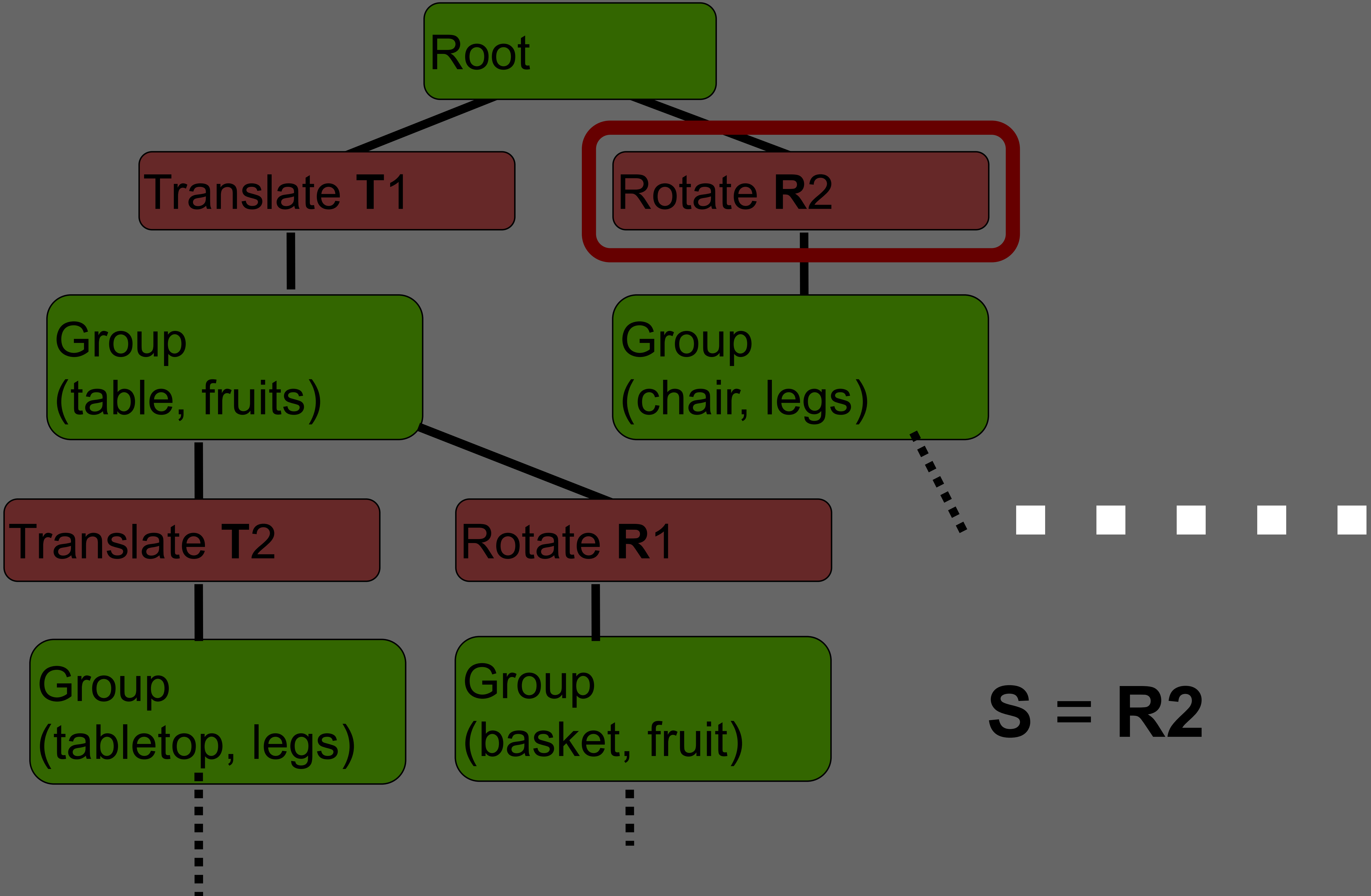
S = **R2**

Traversal Example



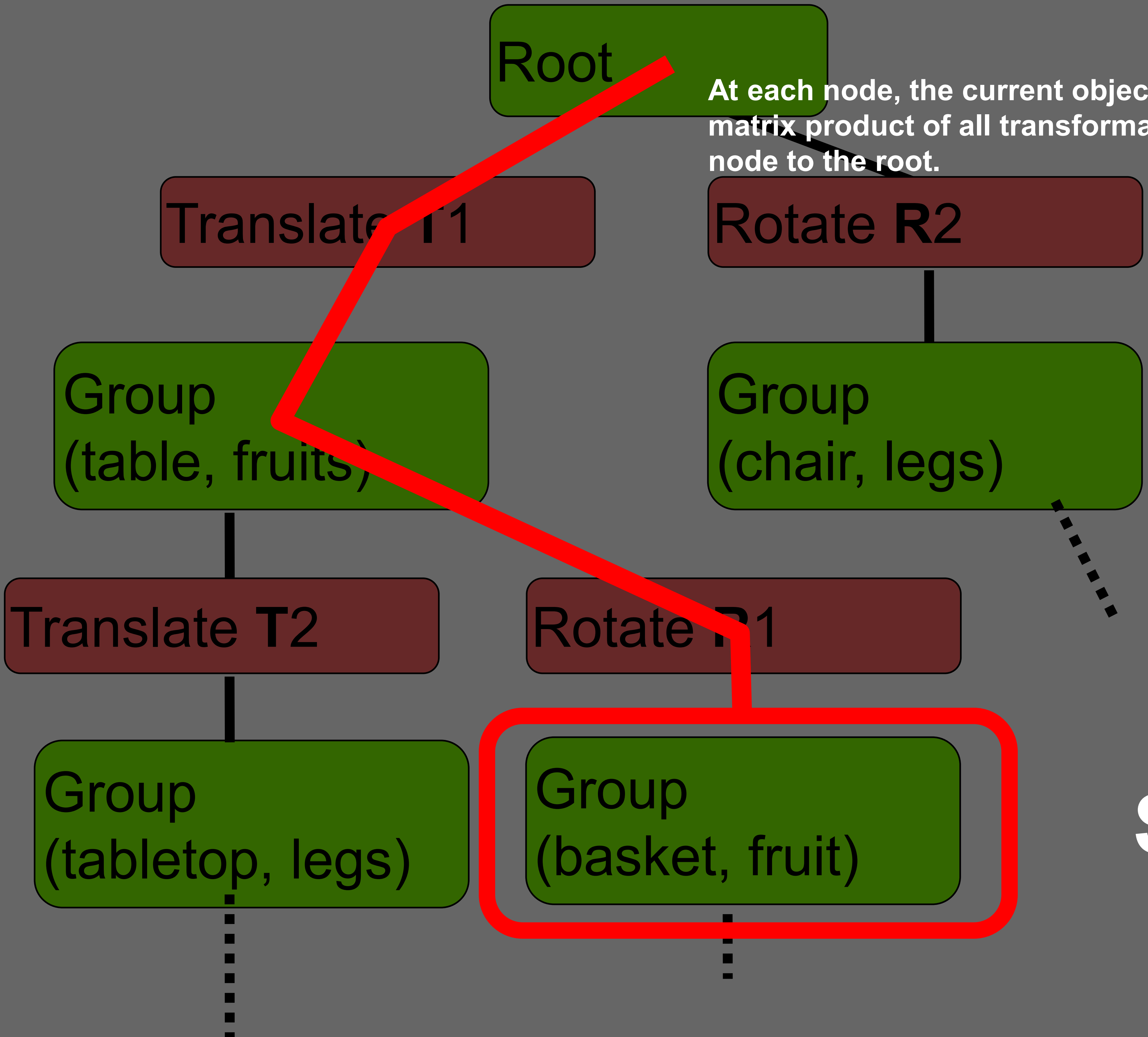
S = **R2**

Traversal Example



S = R2

Traversal Example



At each node, the current object-to-world transformation is the matrix product of all transformations found on the way from the node to the root.

S = T1R1

Traversal State

- The state is updated during traversal
  - Transformations
  - But also other properties (color, etc.)
  - **Apply when entering node, “undo” when leaving

- How to implement?
  - Bad idea to undo transformation by inverse matrix **(Why?)**

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  - Why I? **T***$\mathbf{T}$-1 = **I** does not necessarily hold in floating point even when T is an invertible matrix – you accumulate error
  - Why II? **T** might be singular, e.g., could flatten a 3D object onto a plane – no way to undo, inverse doesn’t exist!

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Can you think of a data structure suited for this?

Traversal State – Stack

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  - But also other properties (color, etc.)
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- How to implement?
  - Bad idea to undo transformation by inverse matrix
  - Why I? **T*****T**-1 = **I** does not necessarily hold in floating point even when T is an invertible matrix – you accumulate error
  - Why II? **T** might be singular, e.g., could flatten a 3D object onto a plane – no way to undo, inverse doesn't exist!
- **Solution:** Keep state variables in a **stack**
  - Push current state when entering node, update current state
  - Pop stack when leaving state-changing node
  - See what the stack looks like in the previous example!

Questions?

Plan

- Hierarchical Modeling, Scene Graph
- OpenGL matrix stack
- Hierarchical modeling and animation of characters
  - Forward and inverse kinematics

Hierarchical Modeling in OpenGL

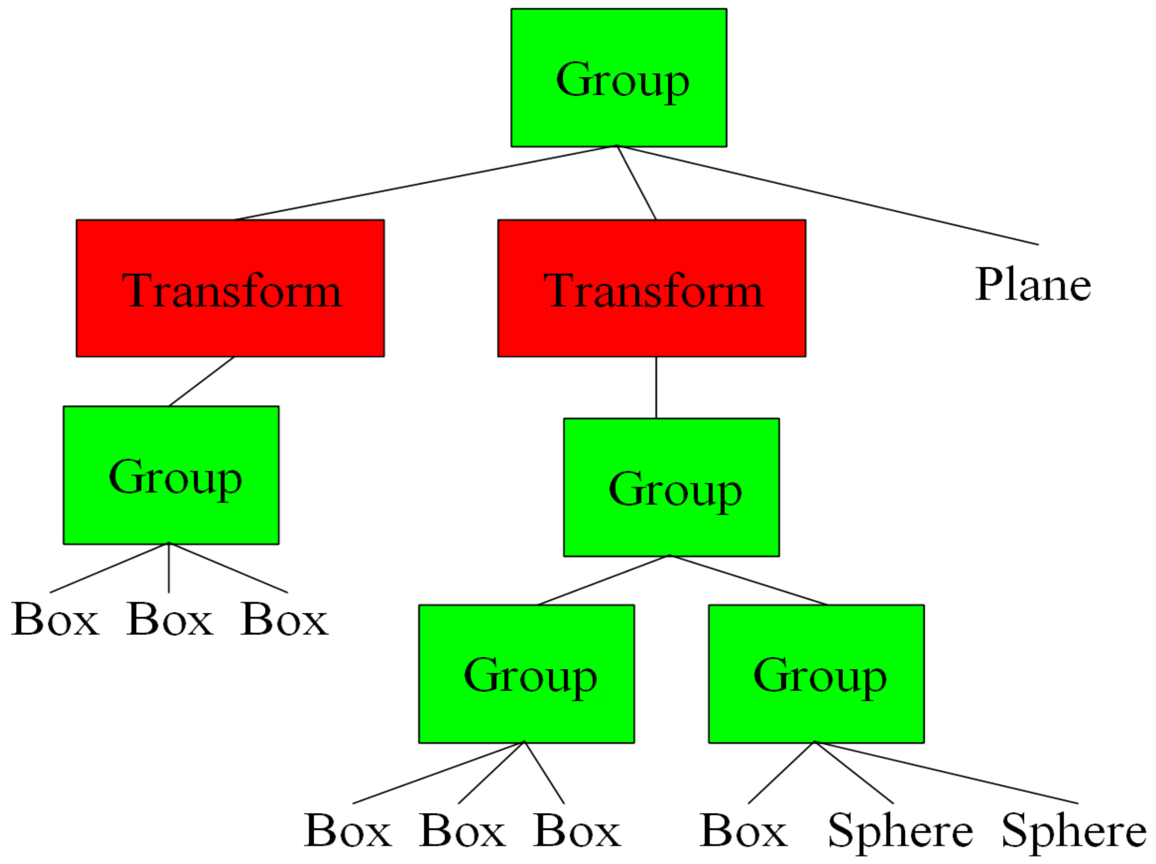
- The OpenGL Matrix Stack implements what we just did!

- Commands to change current transformation
  - glTranslate, glScale, etc.
- Current transformation is part of the OpenGL state, i.e., all following draw calls will undergo the new transformation
  - Remember, a transform affects the whole subtree
- Functions to maintain a matrix stack
  - glPushMatrix, glPopMatrix
- Separate stacks for modelview (object-to-view) and projection matrices

When You Encounter a Transform Node

- Push the current transform using glPushMatrix()
- Multiply current transform by node's transformation
  - Use glMultMatrix(), glTranslate(), glRotate(), glScale(), etc.
- Traverse the subtree
  - Issue draw calls for geometry node
- Use glPopMatrix() when done.

- Simple as that!



More Specifically…

- An OpenGL transformation call corresponds to a matrix **T**
- The call multiplies current modelview matrix **C** by **T** from the right, i.e. **C**′ = **C** * **T**.
  - This also works for projection, but you often set it up only once.

- This means that the transformation for the subsequent vertices will be **p**′ = **C** * **T** * **p**
  - Vertices are column vectors on the right in OpenGL
  - This implements hierarchical transformation directly!

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  - Vertices are column vectors on the right in OpenGL
  - This implements hierarchical transformation directly!

- At the beginning of the frame, initialize the current matrix by the viewing transform that maps from world space to view space.
  - For instance, glLoadIdentity() followed by gluLookAt()

Questions?

- Further reading on OpenGL
  Matrix Stack and hierarchical model/view transforms
  - http://www.glprogramming.com/red/chapter03.html

- It can be a little confusing if you don't think the previous through, but it's really quite simple in the end.
  - I know very capable people who after 15 years of experience still resort to brute force (trying all the combinations) for getting their transformations right, but it's such a waste :)

Plan

- Hierarchical Modeling, Scene Graph
- OpenGL matrix stack
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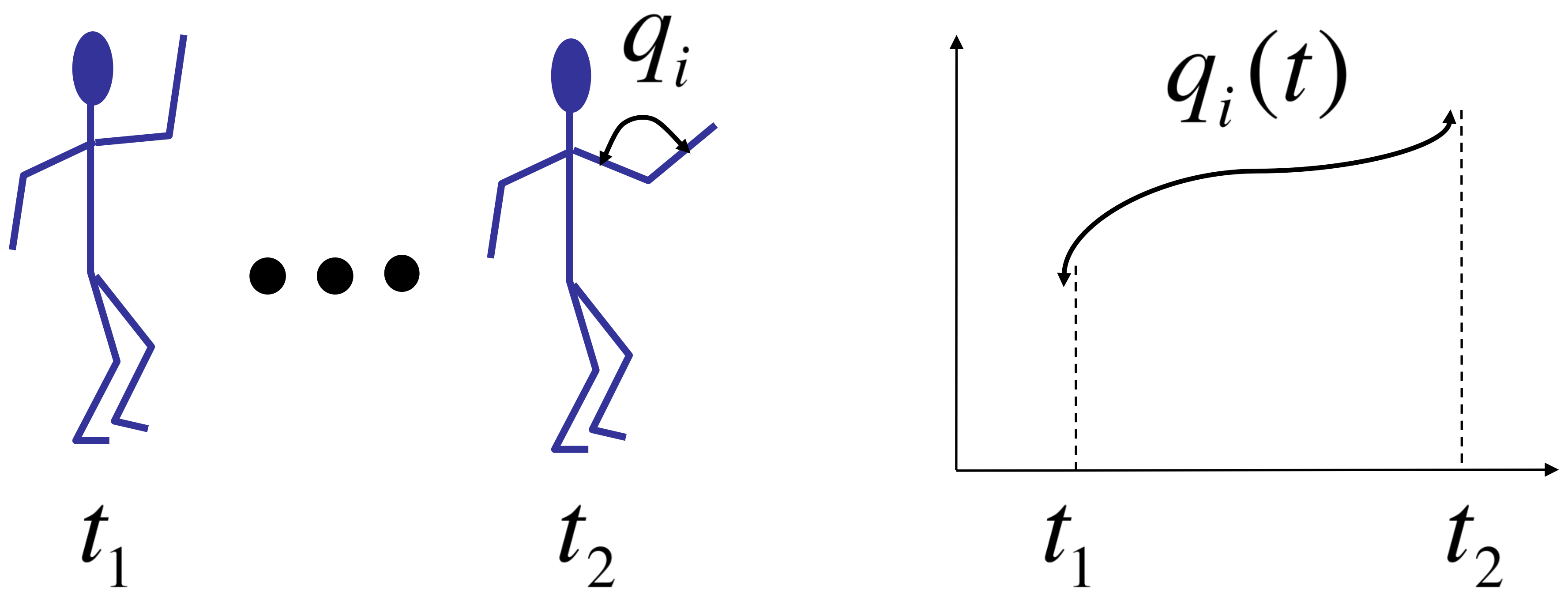
Animation

- Hierarchical structure is essential for animation
  - Eyes move with head
  - Hands move with arms
  - Feet move with legs
  - …
- Without such structure the model falls apart.

Articulated Models

- **Articulated models** are rigid parts connected by joints
  - each joint has some angular degrees of freedom

- Articulated models can be animated by specifying the joint angles as functions of time.

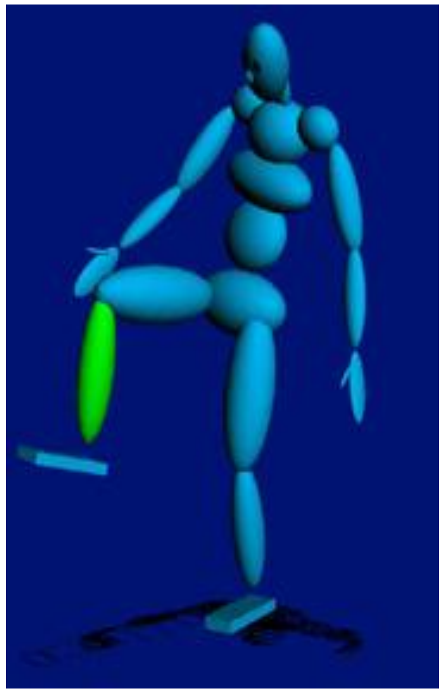


Joints and bones

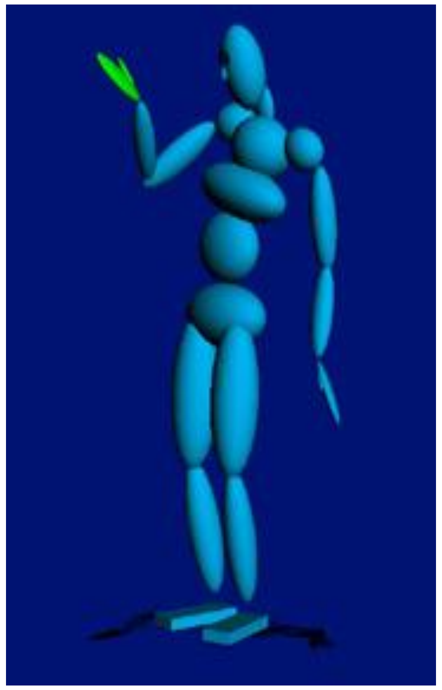
- Describes the positions of the body parts as a function of joint angles.
  - Body parts are usually called "bones"

- Each joint is characterized by its degrees of freedom (dof)
  - Usually rotation for articulated bodies

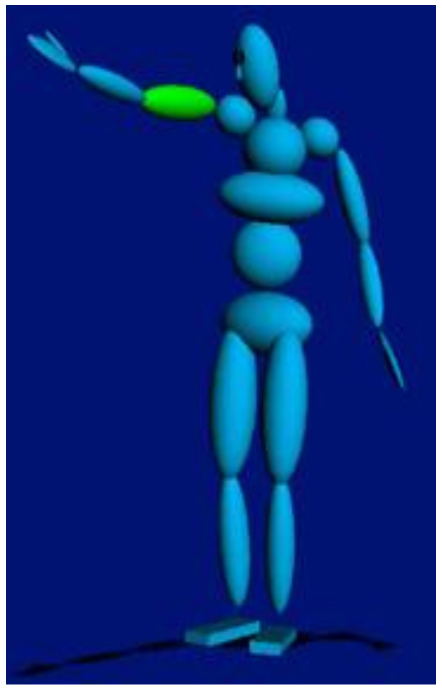
1 DOF: knee



2 DOF: wrist



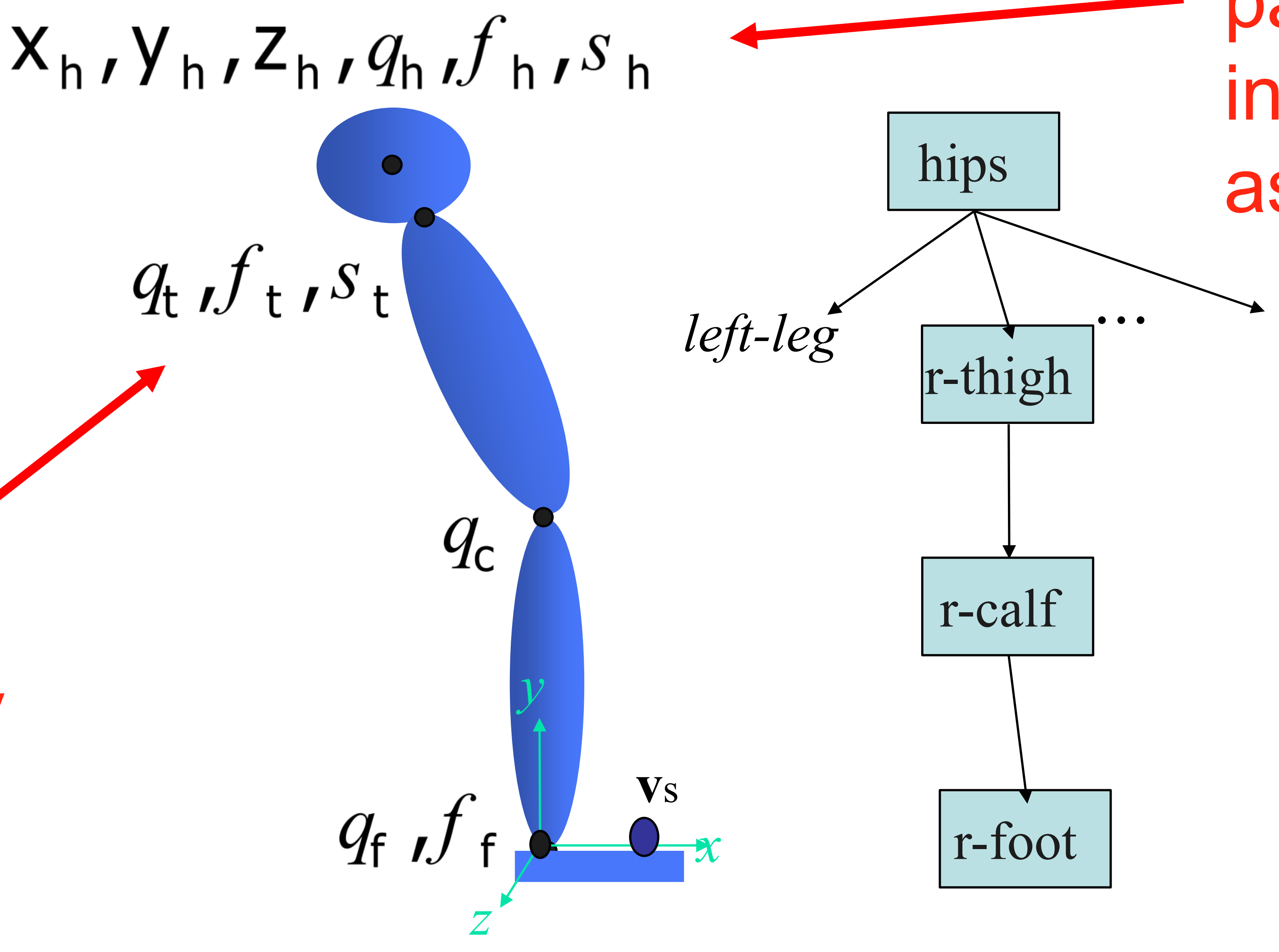
3 DOF: arm



Skeleton Hierarchy

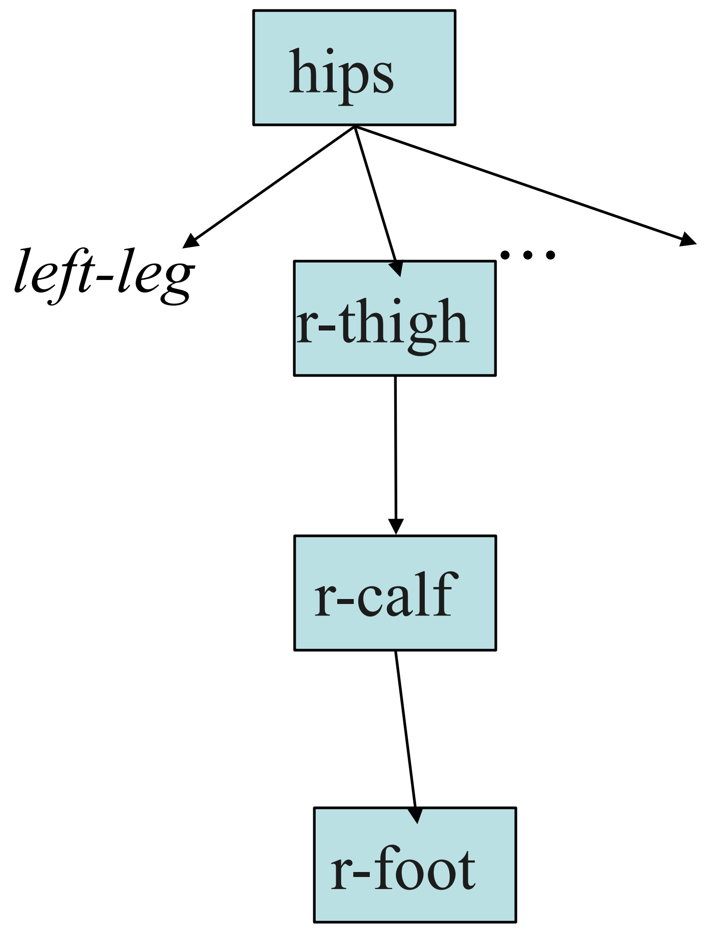
- Each bone position/orientation described relative to the parent in the hierarchy:

For the root, the parameters include a position as well



Joints are specified by angles.

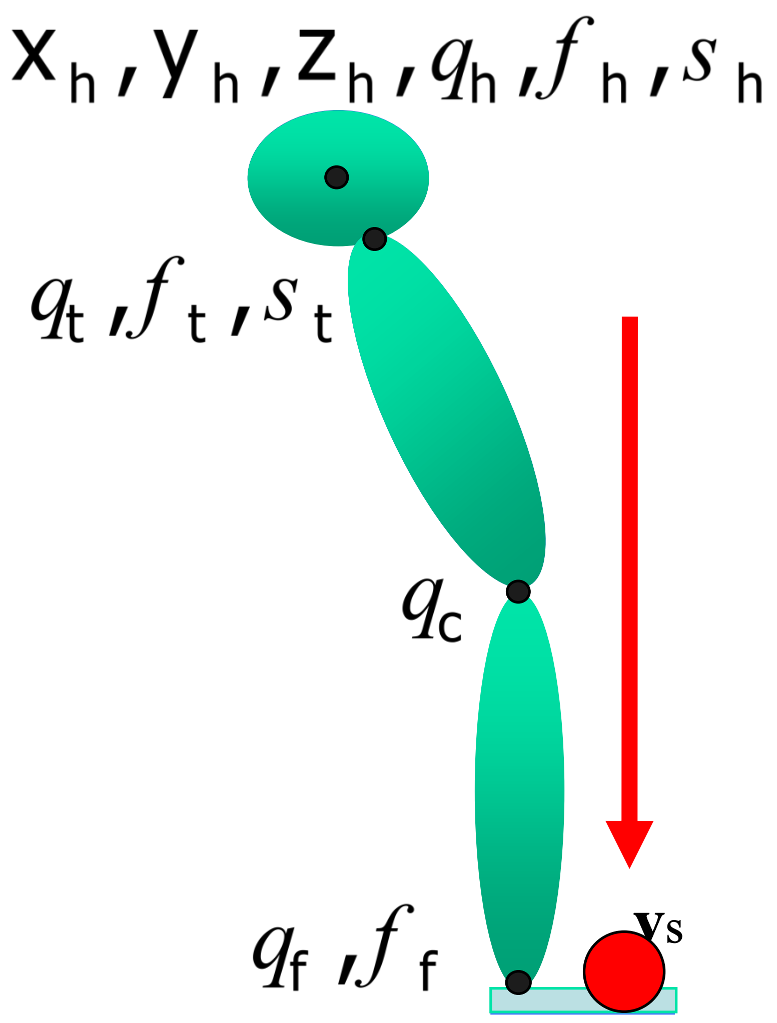
Draw by Traversing a Tree



```
glLoadIdentity();
glPushMatrix();
  glTranslatef(…);
  glRotate(…);
  drawHips();
  glPushMatrix();
    glTranslate(…);
   glRotate(…);
   drawThigh();
   glTranslate(…);
   glRotate(…);
   drawCalf();
   glTranslate(…);
   glRotate(…);
   drawFoot();
  glPopMatrix();
  left-leg
```

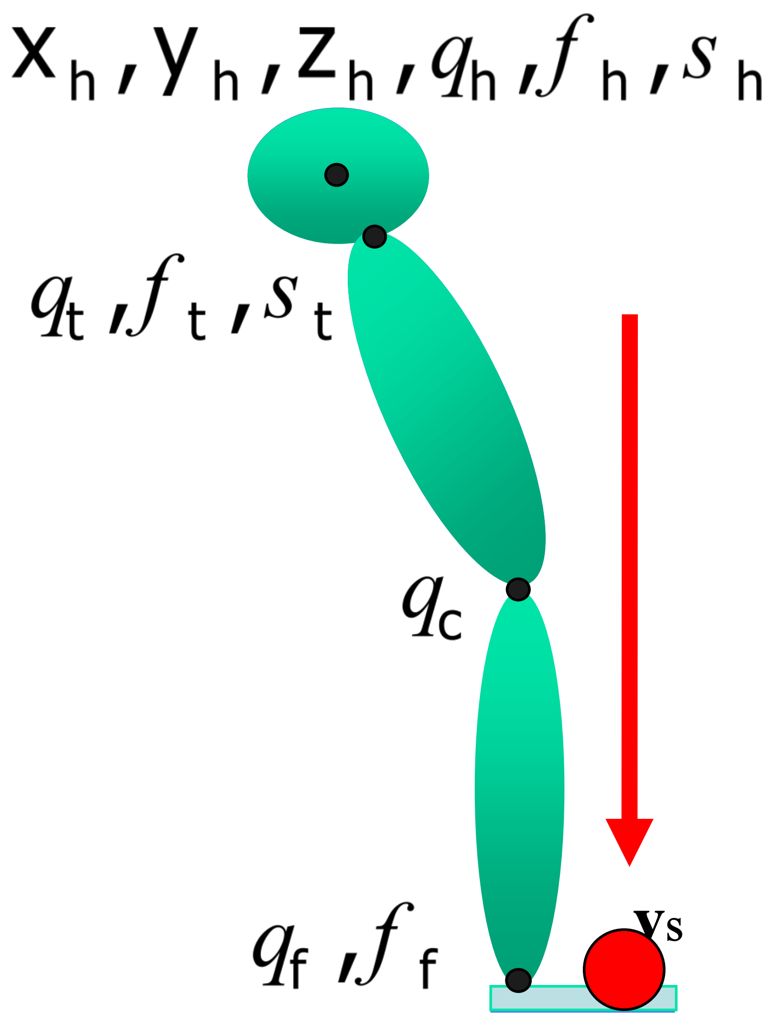
- Assumes drawing procedures for thigh, calf, and foot use joint positions as the origin for a drawing coordinate frame

Forward Kinematics


$x_h, y_h, z_h, \theta_h, \phi_h, \sigma_h$
$\theta_t, \phi_t, \sigma_t$
θ_c
θ_f, ϕ_f
vs

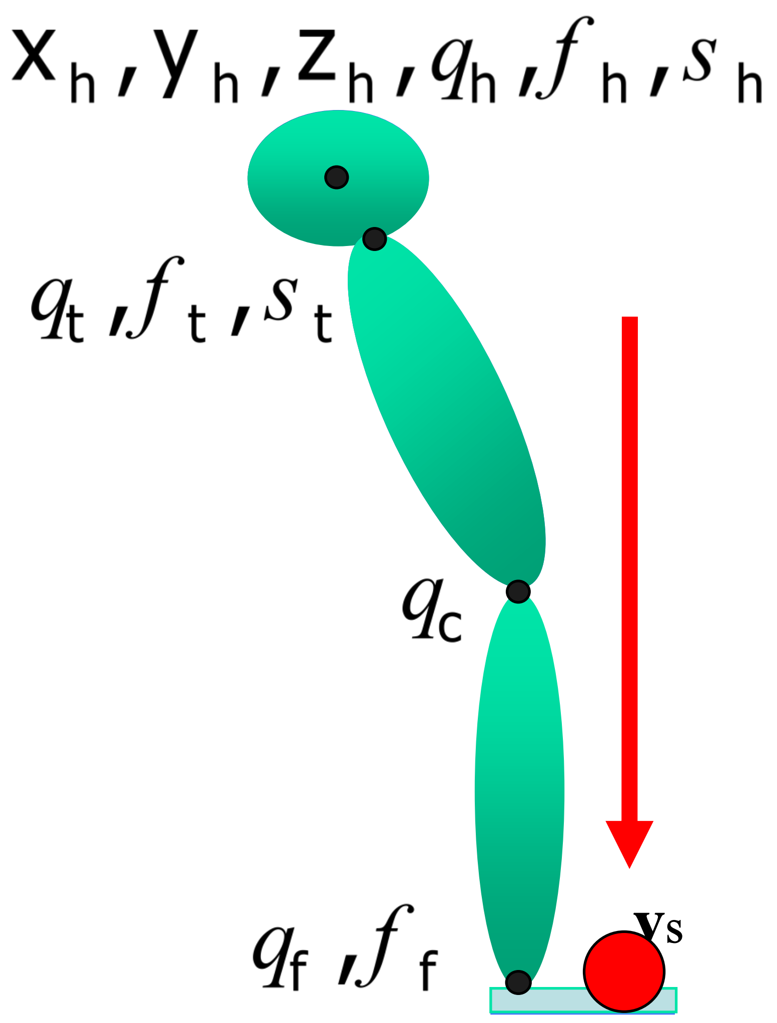
How to determine the world-space position for point **vs**?

Forward Kinematics



Transformation matrix **S** for a point **v**s is a matrix composition of all joint transformations between the point and the root of the hierarchy. **S** is a function of all the joint angles between here and root.

Forward Kinematics



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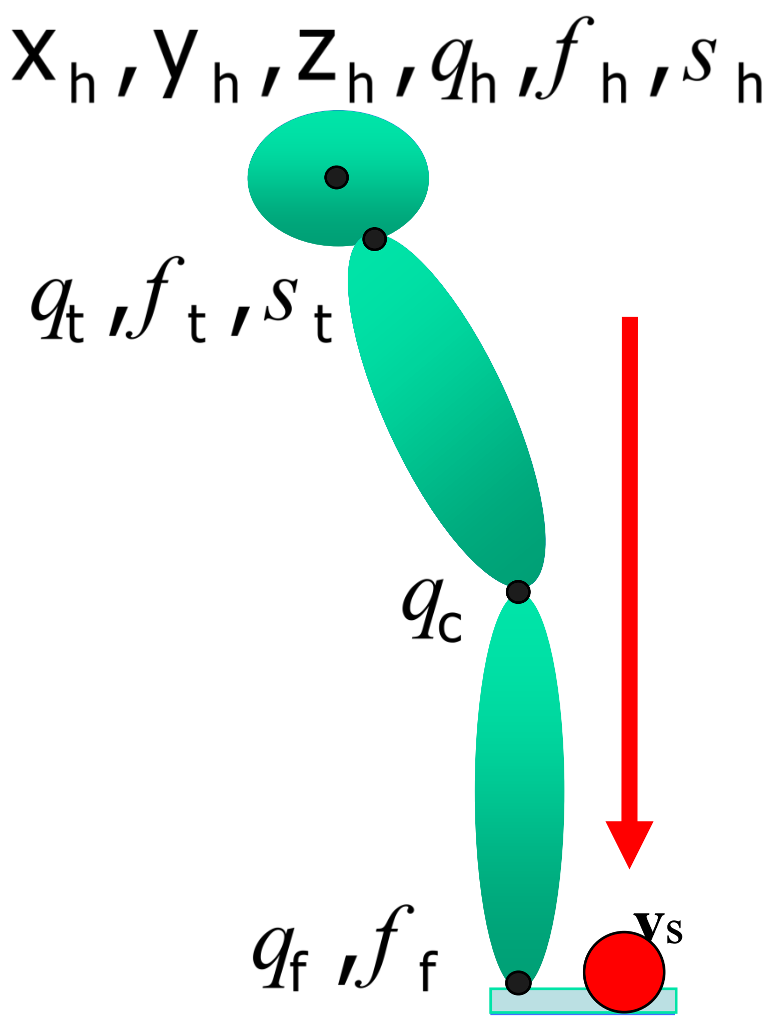
Note that the angles have a non-linear effect.

This product is **S**

$$\mathbf{v}_w = \boxed{\mathbf{T}(x_h,y_h,z_h)\mathbf{R}(q_h,f_h,s_h)\ \mathbf{TR}(q_t,f_t,s_t)\ \mathbf{TR}(q_c)\ \mathbf{TR}(q_f,f_f)}\ \mathbf{v}_s$$

Forward Kinematics



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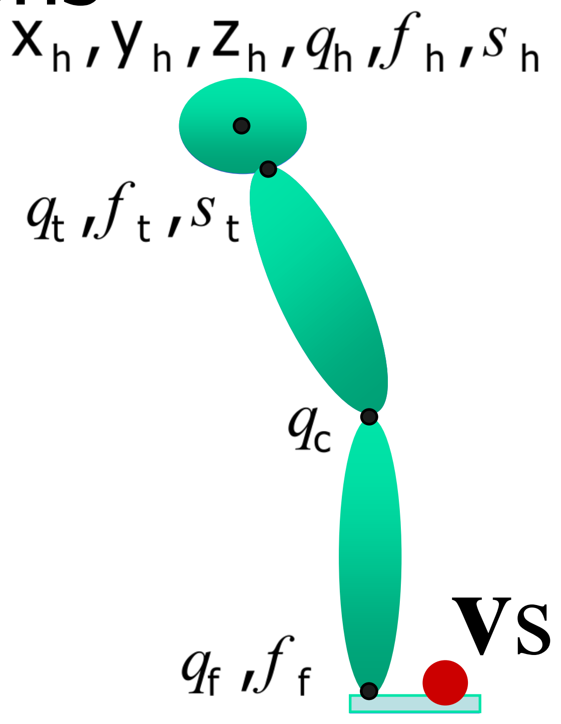
$$v_w = S\left(\underbrace{x_h, y_h, z_h, \theta_h, \phi_h, \sigma_h, \theta_t, \phi_t, \sigma_t, \theta_c, \theta_f, \phi_f}_{p}\right) v_s = S(p) v_s$$

parameter vector **p**

Questions?

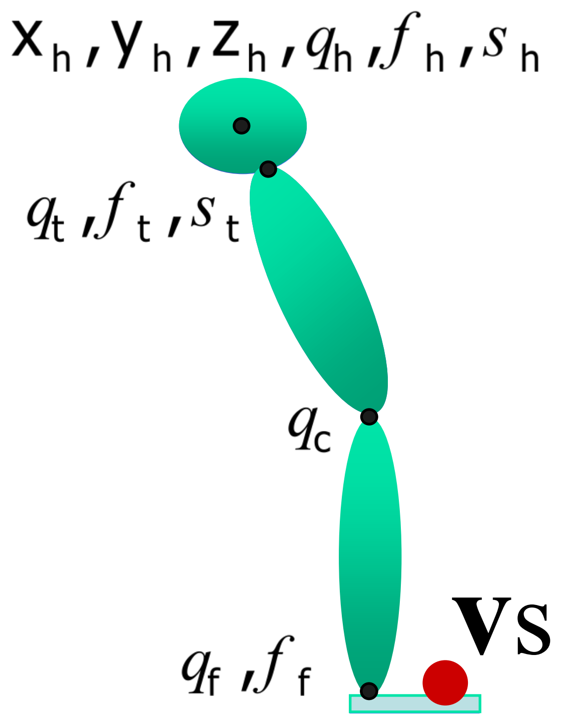
Inverse Kinematics

- Context: an animator wants to "pose" a character
- Specifying every single angle is tedious and not intuitive
- Simpler interface:
  directly manipulate position of e.g. hands and feet
- That is, specify vw, infer joint transformations



Inverse Kinematics

- Forward Kinematics
  - Given the skeleton parameters **p** (position of the root and the joint angles) and the position of the point in local coordinates **v**s, what is the position of the point in the world coordinates **v**w?
  - Not too hard, just apply transform accumulated from the root.



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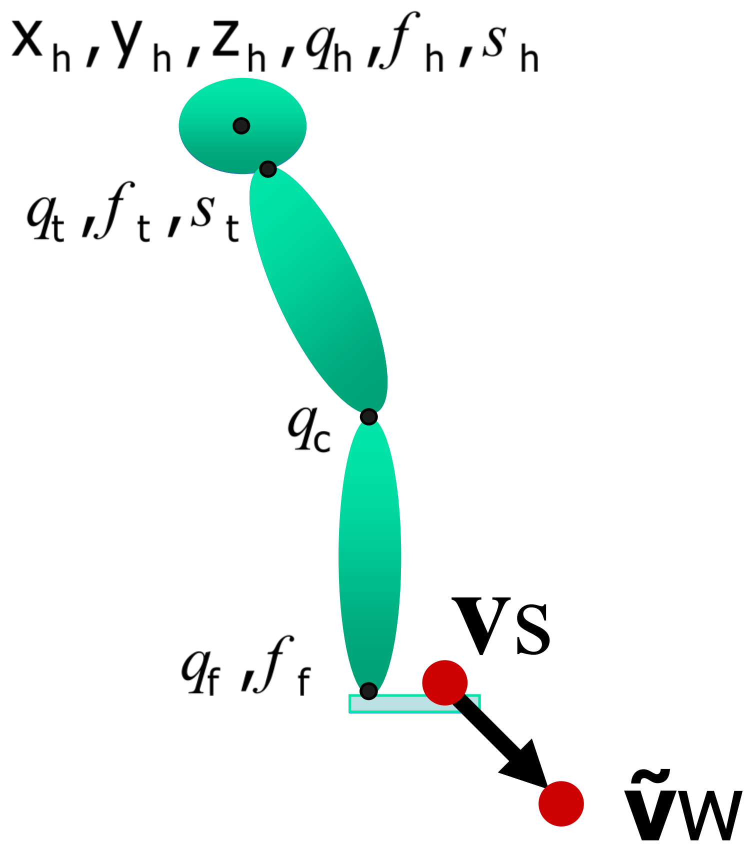
  - Not too hard, just apply transform accumulated from the root.

- Inverse Kinematics
  - Given the current position of the point and the desired new position $\tilde{\mathbf{v}}_w$ in world coordinates, what are the skeleton parameters **p** that take the point to the desired position?



Inverse Kinematics

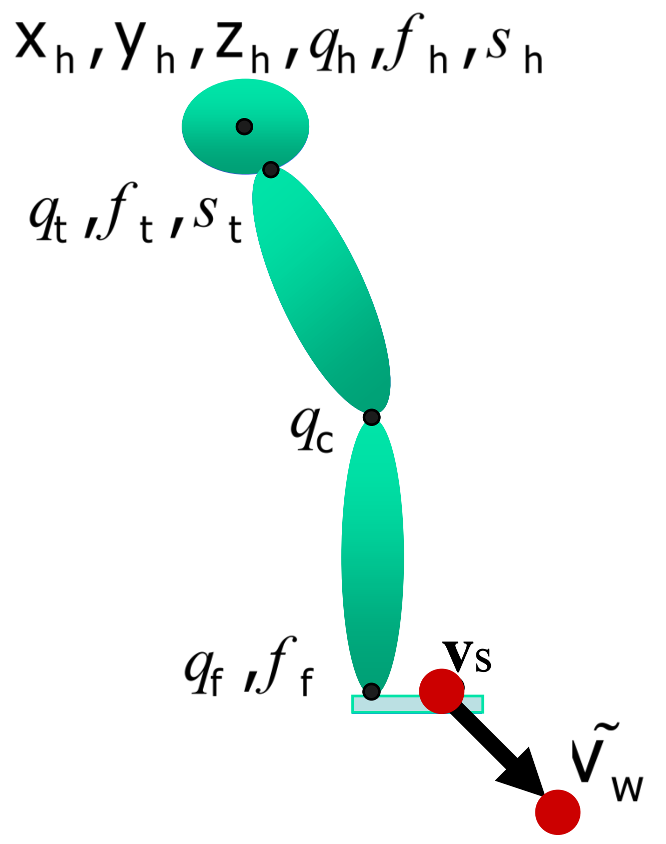
- Given the position of the point in local coordinates **v**s and the desired position $\tilde{\mathbf{v}}_w$ in world coordinates, what are the skeleton parameters **p**?

$$\tilde{v}_w = S\left(\underbrace{x_h, y_h, z_h, \theta_h, \phi_h, \sigma_h, \theta_t, \phi_t, \sigma_t, \theta_c, \theta_f, \phi_f}_{p}\right) v_s = S(p) v_s$$

skeleton parameter vector **p**

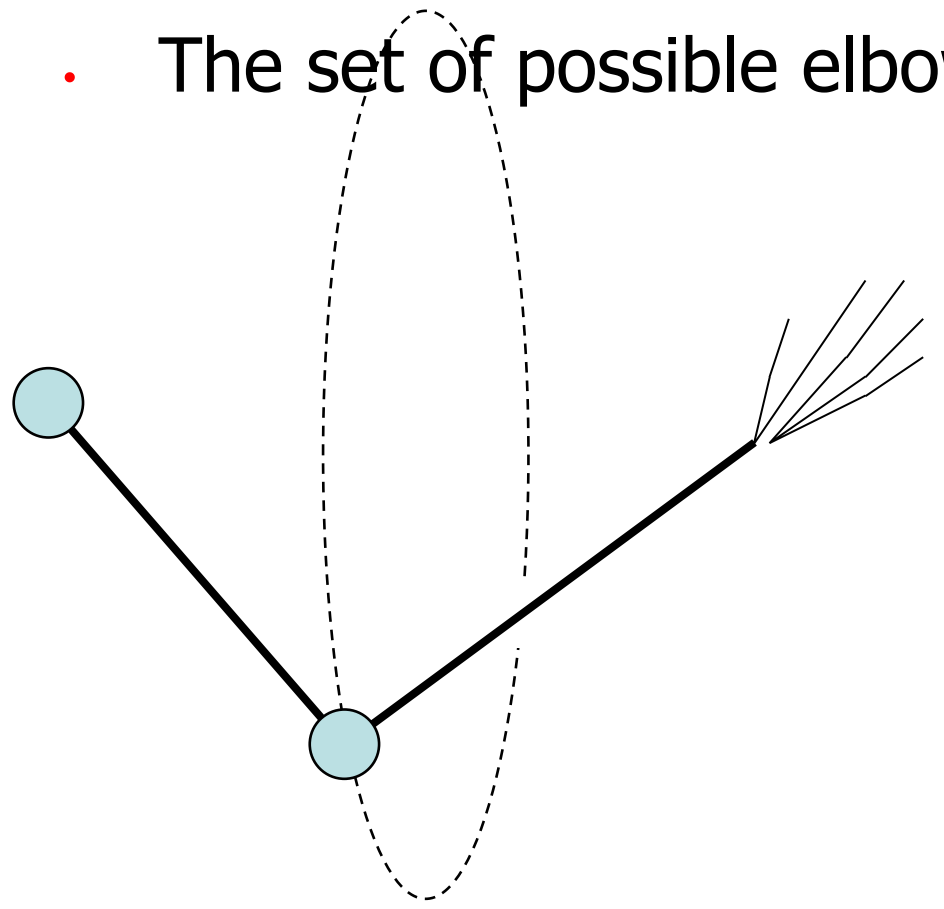
- Requires solving for **p**, given **v**s and $\tilde{\mathbf{v}}_w$
  - Non-linear and …

It’s Underconstrained



- Count degrees of freedom:
  - We specify one 3D point (3 equations)
  - We usually need more than 3 angles
  - **p** usually has tens of dimensions

- Simple geometric example (in 3D): specify hand position, need elbow & shoulder
  - The set of possible elbow location is a circle in 3D



How to tackle these problems?

$$\boldsymbol{v}_{\mathrm{WS}} = \boldsymbol{S}(\boldsymbol{p})\,\boldsymbol{v}_{\mathrm{s}}$$

- Deal with non-linearity:
  Iterative solution (steepest descent)
  - Compute Jacobian matrix of world position w.r.t. angles
    - Jacobian: "If the parameters **p** change by tiny amounts, what is the resulting change in the world position **v**WS?"
  - Then invert Jacobian.
    - This says "if **v**WS changes by a tiny amount, what is the change in the parameters **p**?"
  - But wait! The Jacobian is non-invertible (3xN)
  - Deal with ill-posedness: Pseudo-inverse
    - Solution that displaces things the least
    - See http://en.wikipedia.org/wiki/Moore-Penrose_pseudoinverse
  - Deal with ill-posedness: Prior on "good pose" (more advanced)

$$\left[\frac{\partial(\boldsymbol{v}_{\mathrm{WS}})_i}{\partial p_j}\right]$$

- Additional potential issues: bounds on joint angles, etc.
  - Do not want elbows to bend past 90 degrees, etc.

Example: Style-Based IK

- Video

- Prior on “good pose”

- Link to paper: Grochow, Martin, Hertzmann, Popovic: Style-Based Inverse Kinematics, ACM SIGGRAPH 2004

Mesh-Based Inverse Kinematics

- Video

- Doesn’t even need a hierarchy or skeleton: Figure proper transformations out based on a few example deformations!

- Link to paper:
  Sumner, Zwicker, Gotsman, Popovic: Mesh-Based Inverse Kinematics, ACM SIGGRAPH 2005

That's All for Today!

Further reading

- OpenGL Matrix Stack and hierarchical model/view transforms
  - http://www.glprogramming.com/red/chapter03.html