# Animation II

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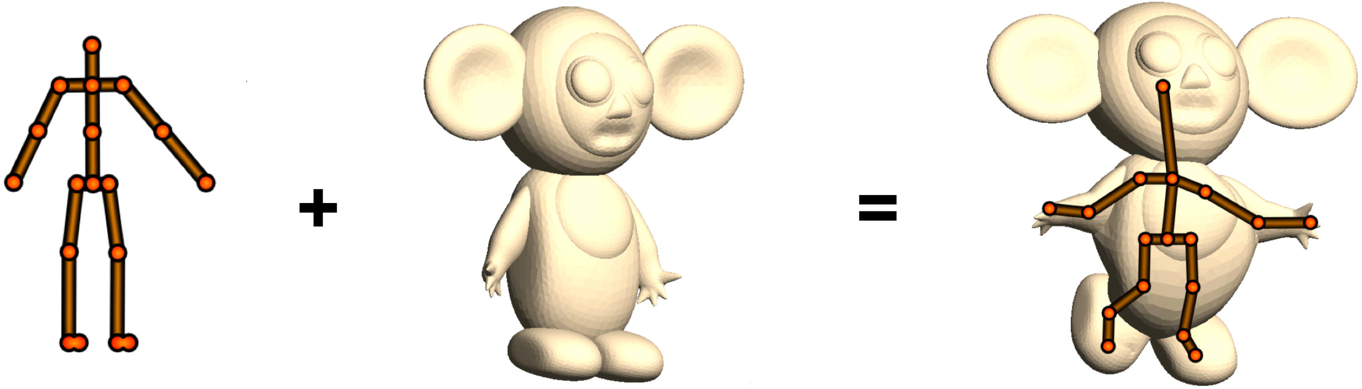
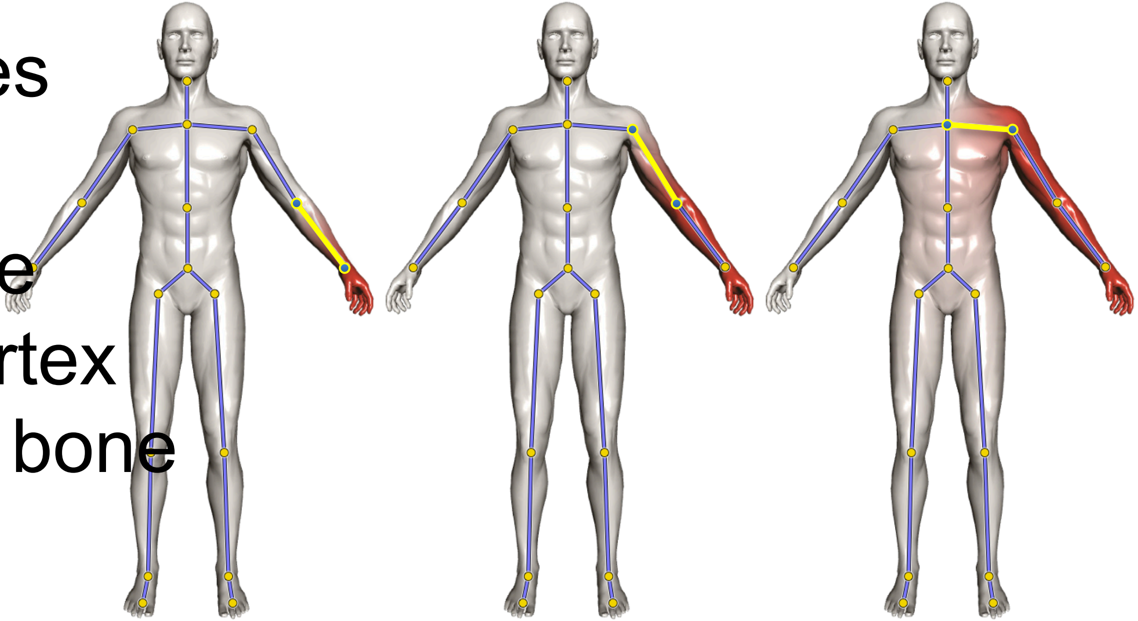
# Character Animation

- Rigging
  - Attaching a skeleton to a model
  - Skeleton is key-framed to animate the model



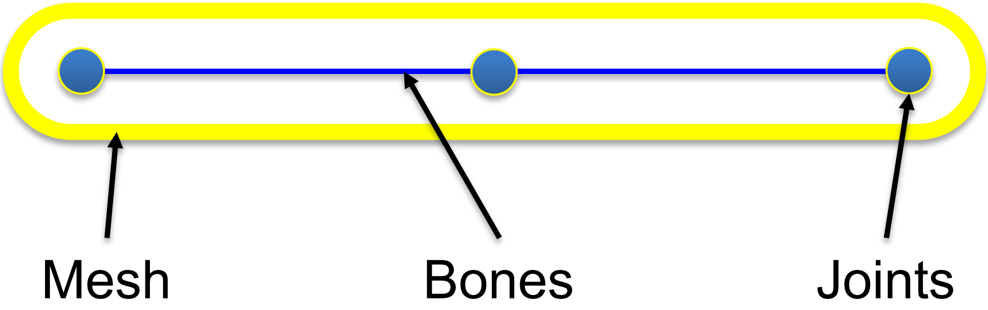
# Character Animation

- Rigging
  - Attach the bones to the model
  - Weights indicate how much a vertex is effected by a bone



# Character Animation

- Rigging
  - Attach the bones to the model

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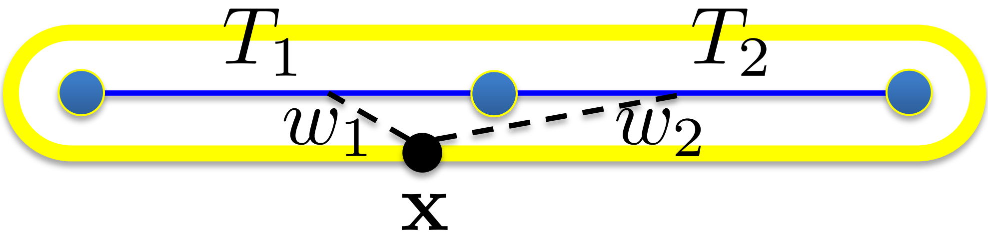
# Character Animation

- Rigging
  - Attach the bones to the model




$$T(\mathbf{x}) = \text{avg}(T_1, T_2, w_1, w_2)$$

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# Character Animation

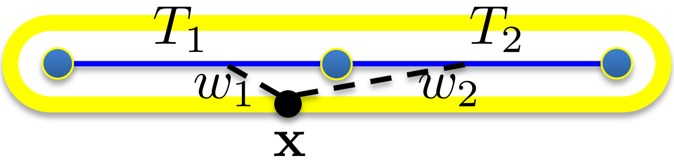
- Rigging
  - How to blend (average) transformations

    Linear Blend Skinning

    Represent $T_i$ with $\mathbf{T}_i$
    in homogenous coordinates

$$\mathbf{T}(\mathbf{x}) = w_1(\mathbf{x})\mathbf{T}_1 + w_2(\mathbf{x})\mathbf{T}_2$$

$$\mathbf{x}' = \mathbf{T}(\mathbf{x})\mathbf{x}$$




$$T(\mathbf{x}) = \mathrm{avg}(T_1, T_2, w_1, w_2)$$

# Blended Rigid Transformations

- How to blend (average) transformations

Linear Blend Skinning

$$w_1 \mathbf{T}_1 + w_2 \mathbf{T}_2$$

$$w_1 \mathbf{t}_1 + w_2 \mathbf{t}_2$$

Translation

$$w_1 \mathbf{R}_1 + w_2 \mathbf{R}_2$$

Rotation

Not a valid rotation matrix!

# Blended Rigid Transformations

- How to blend (average) transformations

Valid rotation matrix

$$\mathbf{R}^T = \mathbf{R}^{-1}$$
$$\det(\mathbf{R}) = 1$$

Linear blending

$$(w_1\mathbf{R}_1 + w_2\mathbf{R}_2)^T$$
$$= (w_1\mathbf{R}_1^T + w_2\mathbf{R}_2^T)$$
$$\neq (w_1\mathbf{R} + w_2\mathbf{R})^{-1}$$

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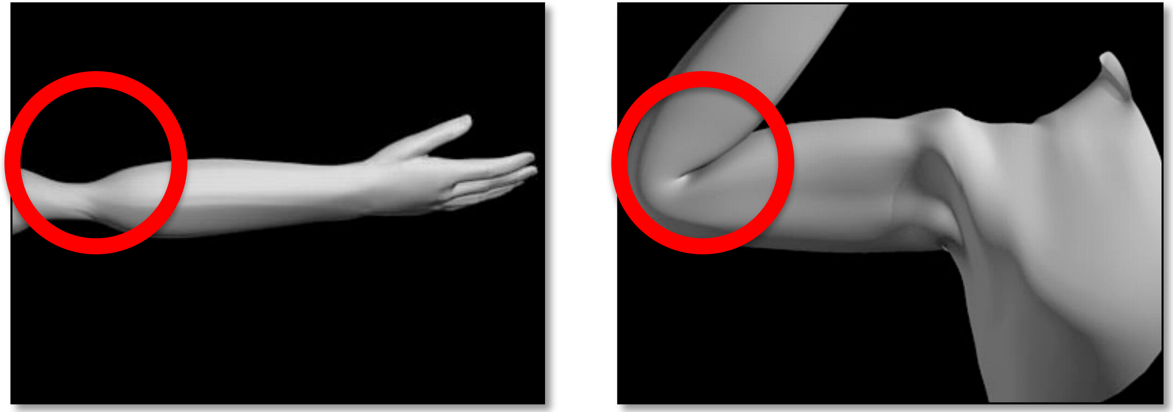
# Blended Rigid Transformations

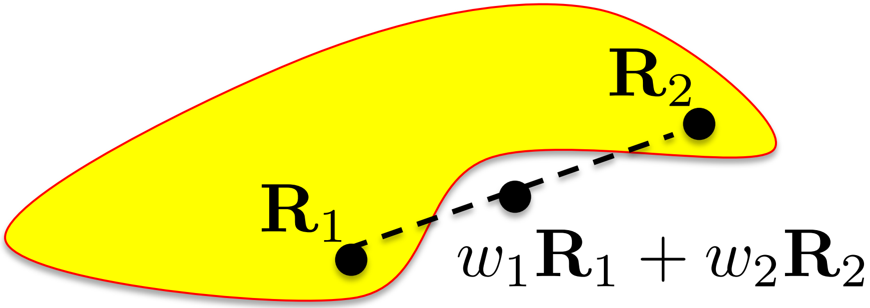
- How to blend (average) transformations

Linear Blend Skinning: problems



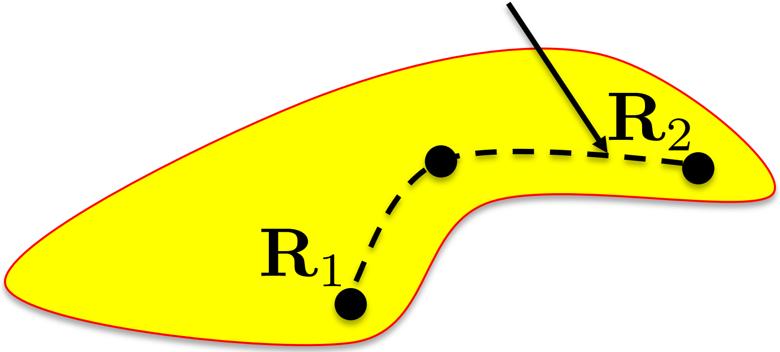
# Blended Rigid Transformations

- How to blend transformations




Manifold of rigid transformations

Shortest path on the manifold




Manifold of rigid transformations

# Rigid Transformations

- Manifold of rotations – SO (3)

Valid rotation matrix

$$\mathbf{R}^T = \mathbf{R}^{-1}$$
$$\det(\mathbf{R}) = 1$$

- Manifold of rigid transformations – SE (3)

$$\mathbf{R}^T = \mathbf{R}^{-1}$$
$$\det(\mathbf{R}) = 1$$

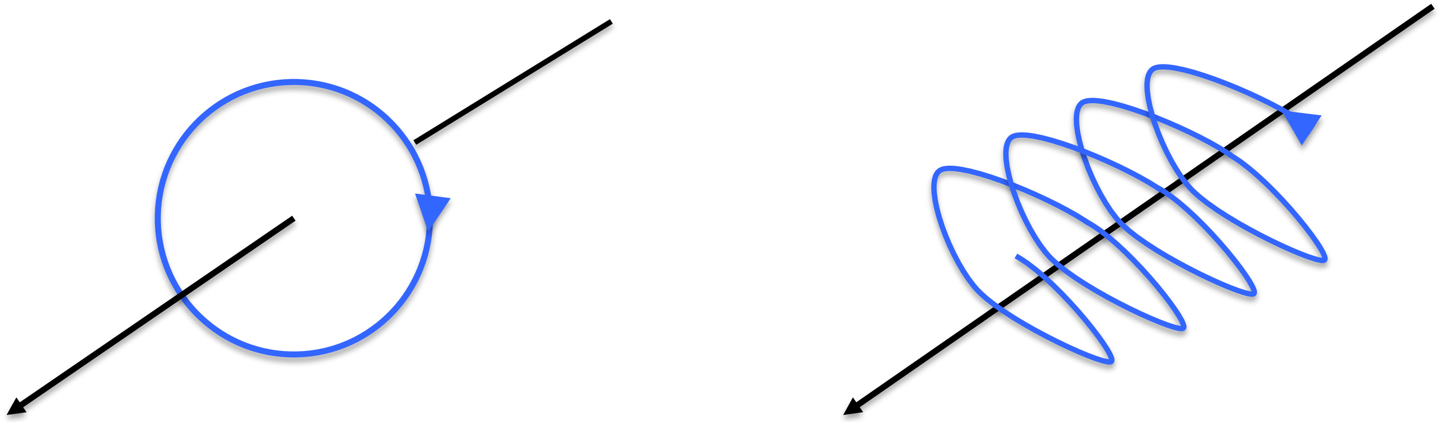
$$\mathbf{T} = \begin{pmatrix} \mathbf{R} & \mathbf{t} \\ 0\;0\;0 & 1 \end{pmatrix}$$

# Rigid Transformations

- Matrices not convenient for blending
- Alternative representation: dual quaternions

# Rigid Transformations

- Representing rigid transformations



Rotations with quaternions

Rigid motions with dual quaternions

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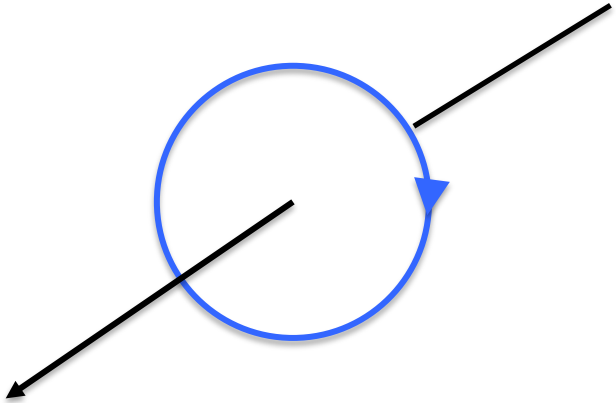
# Rotations

- Representing rotations with quaternions

$$\mathbf{q} = \cos\left(\frac{\theta}{2}\right) + \mathbf{s}\sin\left(\frac{\theta}{2}\right)$$

Quaternion Rotation angle Rotation axis



Rotations with quaternions

# Rotations

- Quaternions

$$\mathbf{q} = \cos\left(\frac{\theta}{2}\right) + \mathbf{s}\sin\left(\frac{\theta}{2}\right)$$

$$\mathbf{s} = s_i i + s_j j + s_k k$$

$$s_i^2 + s_j^2 + s_k^2 = 1$$

$$i^2 = j^2 = k^2 = ijk = -1$$

# Rotations

- Operations on quaternions

$$\mathbf{q} = \cos\left(\frac{\theta}{2}\right) + \mathbf{s}\sin\left(\frac{\theta}{2}\right)$$

Conjugate

$$\mathbf{q}^* = \cos\left(\frac{\theta}{2}\right) - \mathbf{s}\sin\left(\frac{\theta}{2}\right) = \cos\left(-\frac{\theta}{2}\right) + \mathbf{s}\sin\left(-\frac{\theta}{2}\right)$$

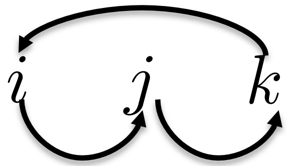
Inverse (for unit quaternions) $\mathbf{q}^{-1} = \mathbf{q}^*$

# Rotations

- Operations on quaternions

Multiplication

$$\mathbf{q}_1\mathbf{q}_2 = (a_1 + b_1 i + c_1 j + d_1 k)(a_2 + b_2 i + c_2 j + d_2 k)$$




Norm

$$||\mathbf{q}||^2 = \mathbf{q}\mathbf{q}^* = \cos^2\left(\frac{\theta}{2}\right) + ||s||^2 \sin^2\left(\frac{\theta}{2}\right) = 1$$

# Rotations

- Operations on quaternions

$$\mathbf{q} = \cos\left(\frac{\theta}{2}\right) + \mathbf{s}\sin\left(\frac{\theta}{2}\right)$$

Power

$$\mathbf{q}^t = e^{t \log \mathbf{q}}$$

$$\log \mathbf{q} = \frac{\theta}{2}\mathbf{s} \qquad e^{\mathbf{q}} = \cos||\mathbf{q}|| + \frac{\mathbf{q}}{||\mathbf{q}||}\sin||\mathbf{q}||$$

# Rotations

- Operations on quaternions

$$\mathbf{q} = \cos\left(\frac{\theta}{2}\right) + \mathbf{s}\sin\left(\frac{\theta}{2}\right)$$

Applying to location vectors

$$\mathbf{v} = v_i i + v_j j + v_k k$$

$$\mathbf{v}' = \mathbf{q}\mathbf{v}\mathbf{q}^*$$

# Rotations

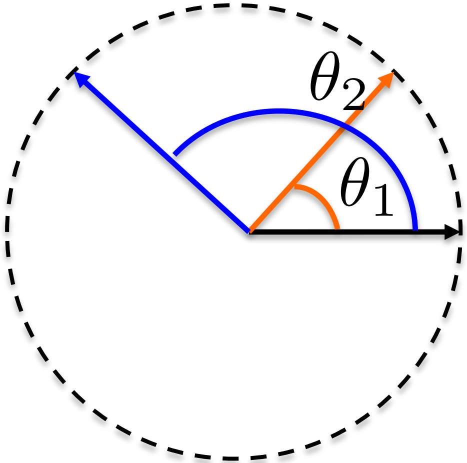
- Blending quaternions

$$\mathbf{s} = \mathbf{s}_1 = \mathbf{s}_2$$

$$\text{interpolate}(\mathbf{q}_1, \mathbf{q}_2, t)$$

$$\theta(t) = (1-t)\theta_1 + t\theta_2$$

$$\mathbf{q}(t) = \cos\left(\frac{\theta(t)}{2}\right) + \mathbf{s}\sin\left(\frac{\theta(t)}{2}\right)$$



# Rotations

- Blending quaternions
  - In general, $\mathbf{s}_1 \neq \mathbf{s}_2$
  - Spherical blending

$$(\mathbf{q}_2\mathbf{q}_1^*)^t\mathbf{q}_1$$

  - More than two rotations?

# Rotations

- Blending quaternions

$$\mathbf{q}_1 \cdots \mathbf{q}_n \quad w_1 \cdots w_n$$

  – Good approximation:

$$\mathbf{b} = \sum_{i=1}^{n} w_i \mathbf{q}_i$$

# Rigid Transformations

- Rotation & translation
- Dual numbers

$$\hat{x} = x_0 + \epsilon x_\epsilon \quad \epsilon^2 = 0$$

E.g. multiplication

$$(a_0 + \epsilon a_\epsilon)(b_0 + \epsilon b_\epsilon)$$
$$= a_0 b_0 + \epsilon(a_0 b_\epsilon + a_\epsilon b_0)$$

# Rigid Transformations

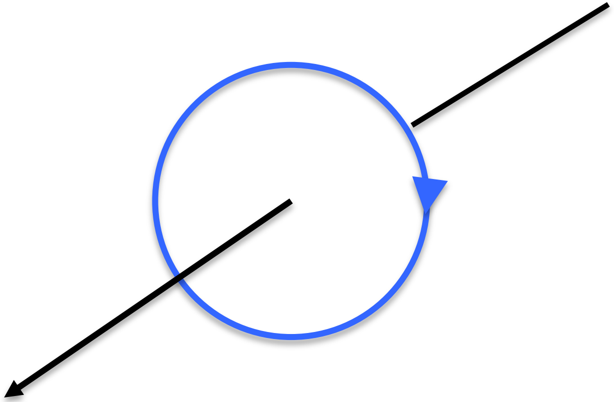
- Dual quaternions
  - Replace numbers in quaternions with dual numbers

$$\hat{\mathbf{q}} = \cos\left(\frac{\hat{\theta}}{2}\right) + \hat{\mathbf{s}}\sin\left(\frac{\hat{\theta}}{2}\right)$$

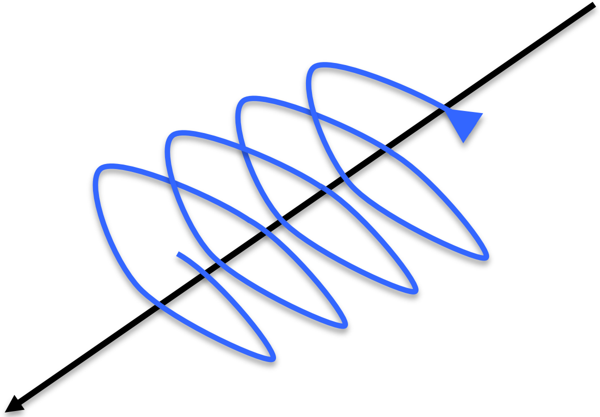
  - Almost all operations & notations are the same
  - In particular: $\hat{\mathbf{b}} = \sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i$

# Rigid Transformations

- Representing rigid transformations



Quaternions : 4 numbers



Dual quaternions : 8 numbers

# Blended Rigid Transformations

- Properties

$$\hat{\mathbf{b}} = \sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i$$

1. Generates valid transformations
   - Only if normalized!

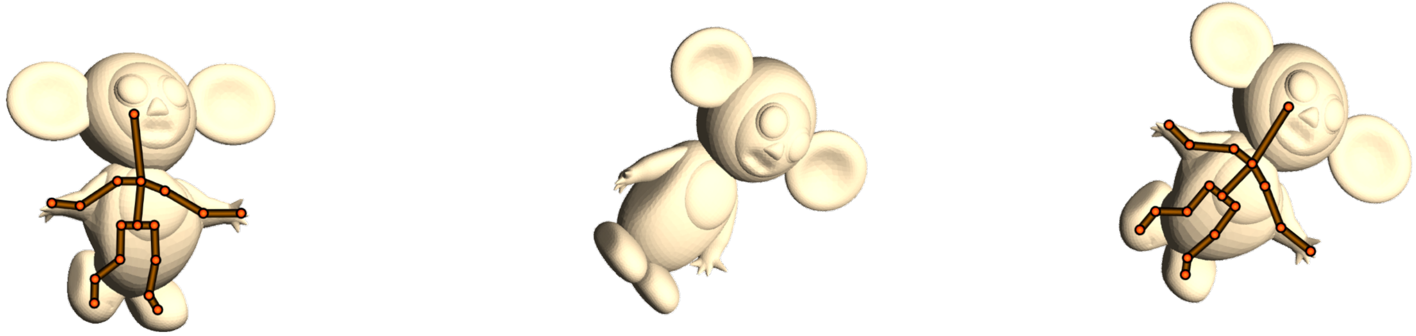
$$\hat{\mathbf{b}} = \frac{\sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i}{||\sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i||}$$

# Blended Rigid Transformations

- Properties

$$\hat{\mathbf{b}} = \frac{\sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i}{||\sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i||}$$

2. Coordinate invariance

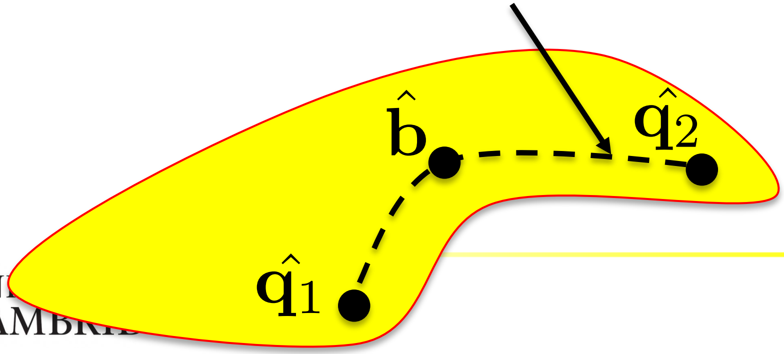


# Blended Rigid Transformations

- Properties

$$\hat{\mathbf{b}} = \frac{\sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i}{||\sum_{i=1}^{n} w_i \hat{\mathbf{q}}_i||}$$

3. Shortest path on SE (3)




$\hat{\mathbf{b}}$, $\hat{\mathbf{q}}_2$, $\hat{\mathbf{q}}_1$

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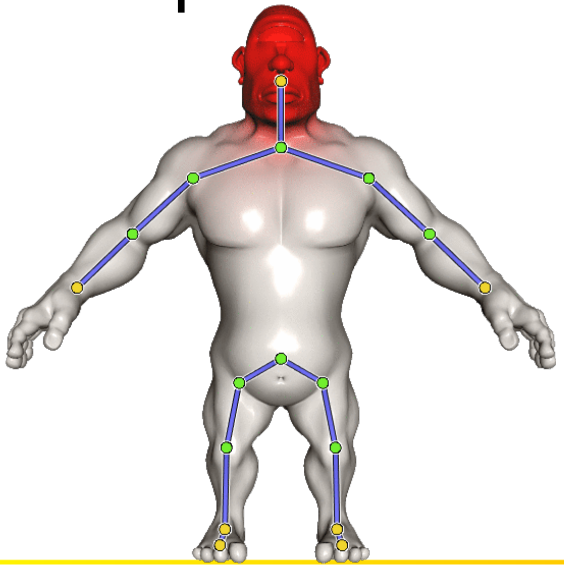
# Blended Rigid Transformations

- Challenges
  - Blending transformations – dual quaternions
  - Weights $w_i(\mathbf{x})$
    - Shape adaptive
    - Intuitive deformations
    - Smooth deformations

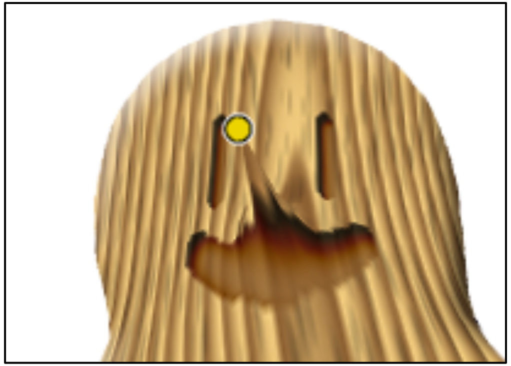


# Blended Rigid Transformations

- Weights – desired properties
  - Partition of unity

$$\sum_{i=1}^{n} w_i(\mathbf{x}) = 1$$

  - Smoothness



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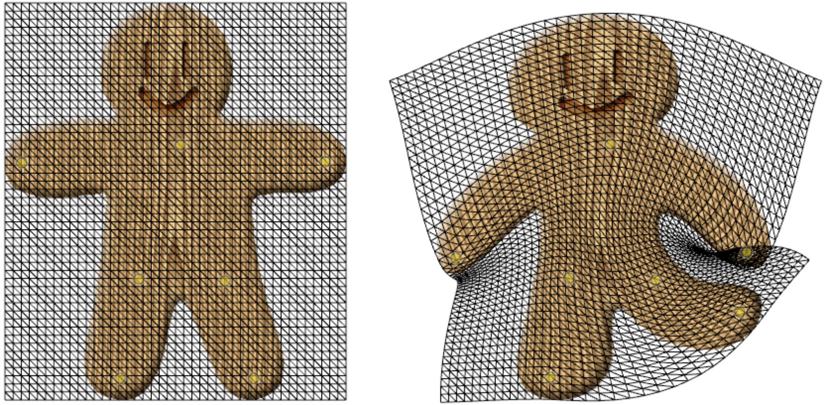
# Blended Rigid Transformations

- Weights – desired properties
  - Shape-awareness

Shape-aware weights



Shape-unaware weights