UC San Diego

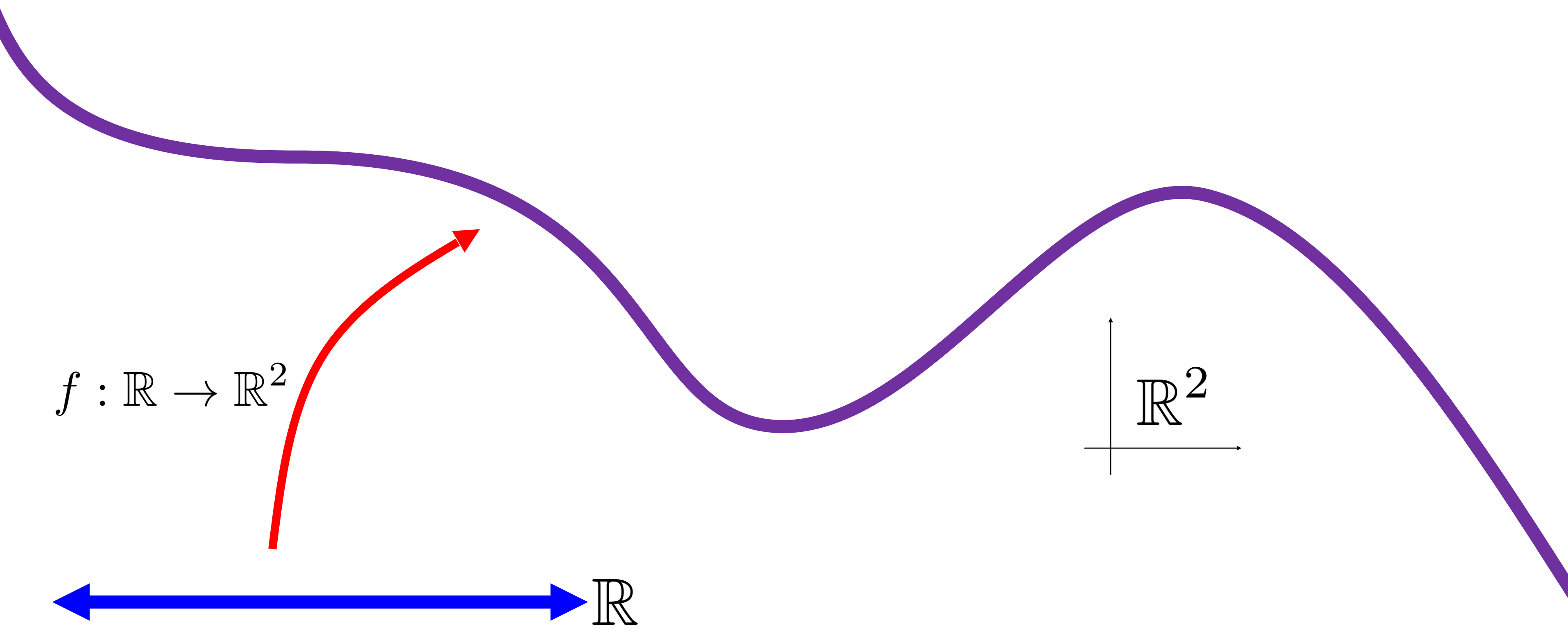
CSE291-C00

Curves: Continuous and Discrete

Instructor: Hao Su

Credit: Justin Solomon

Defining “Curve”



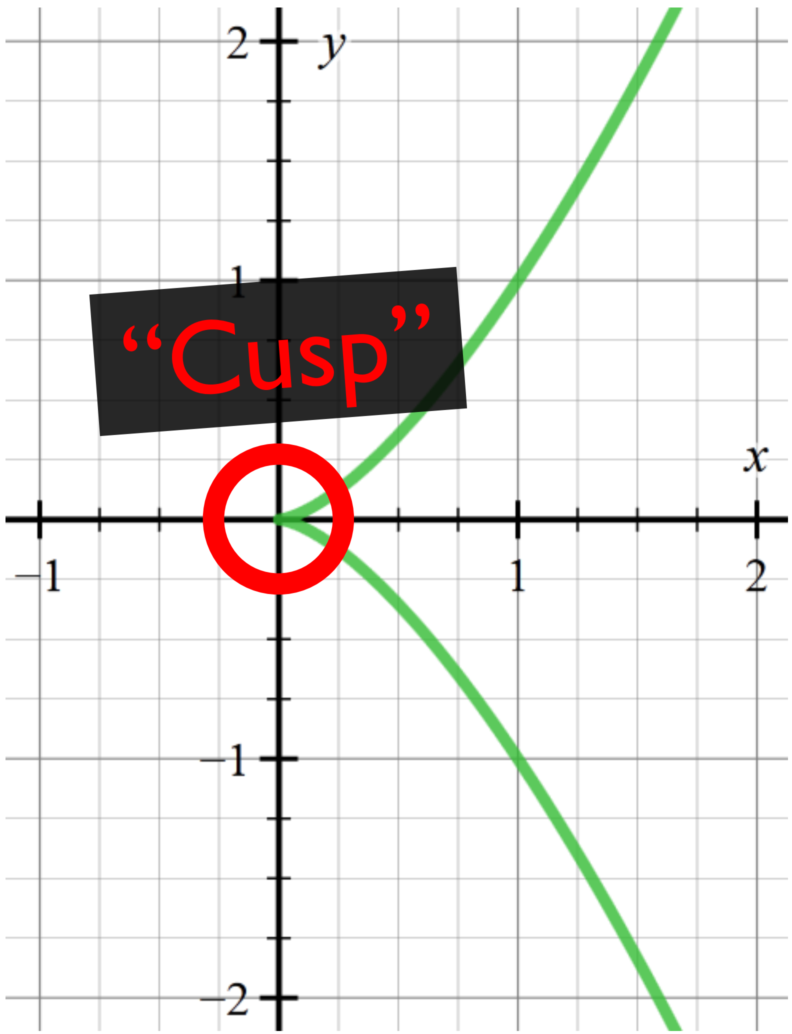
A function?

Subtlety

$$\gamma_3(t) := (0, 0)$$

Not a curve

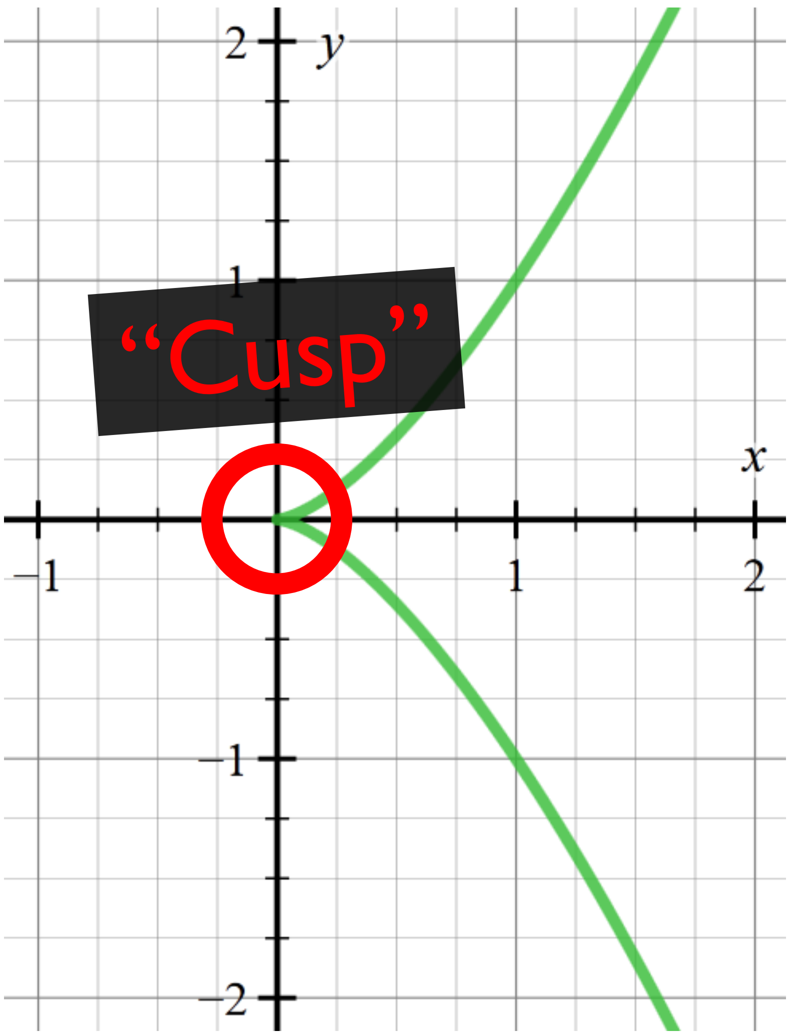
Graphs of Smooth Functions



$$f(t) = (t^2, t^3)$$

http://en.wikipedia.org/wiki/Singular_point_of_a_curve

Graphs of Smooth Functions



$$f(t) = (t^2, t^3)$$

How to ensure the smoothness of a curve?

http://en.wikipedia.org/wiki/Singular_point_of_a_curve

Geometry of a Curve

A curve is a

set of points

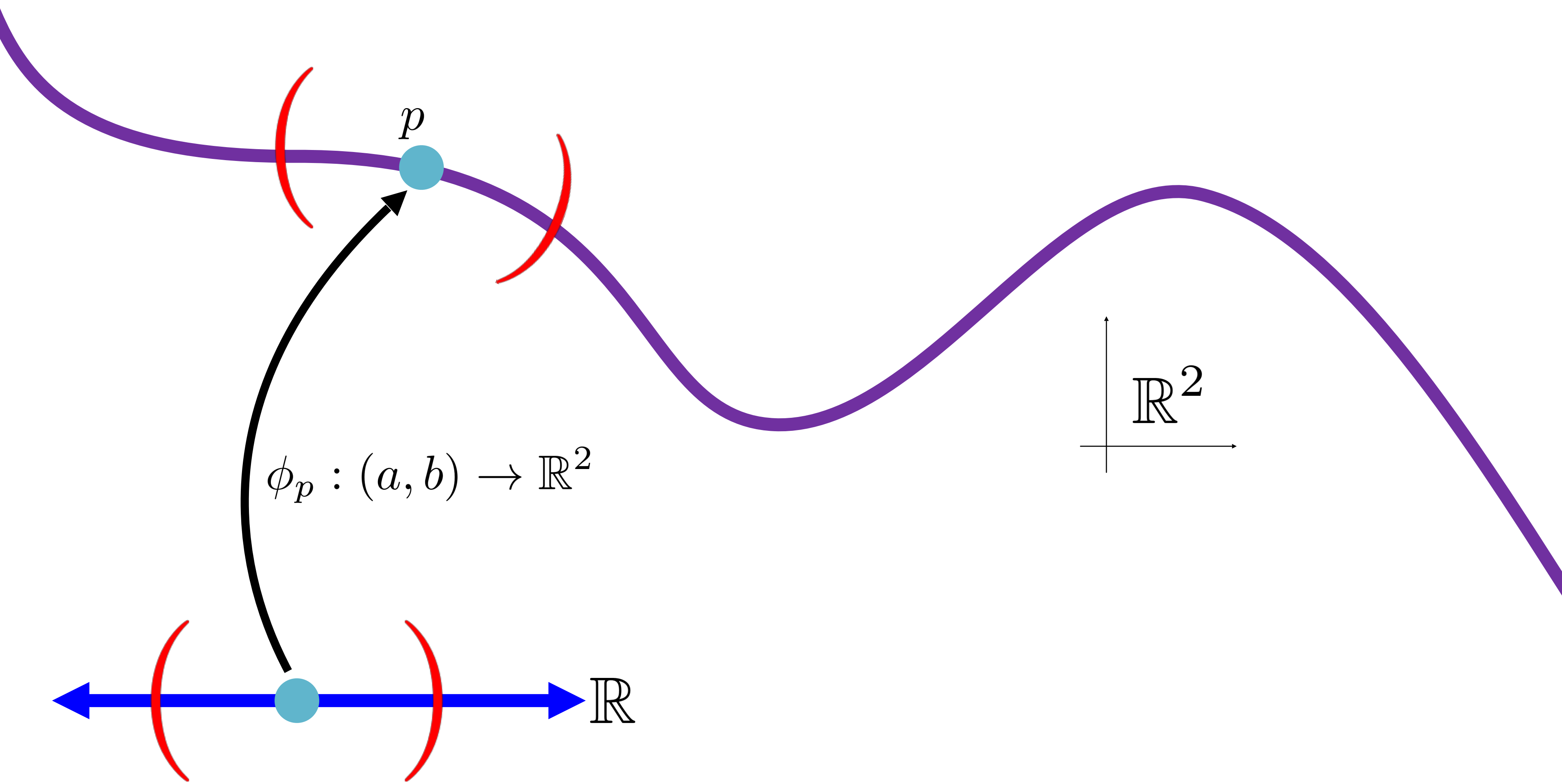
with certain properties.

It is not a function.

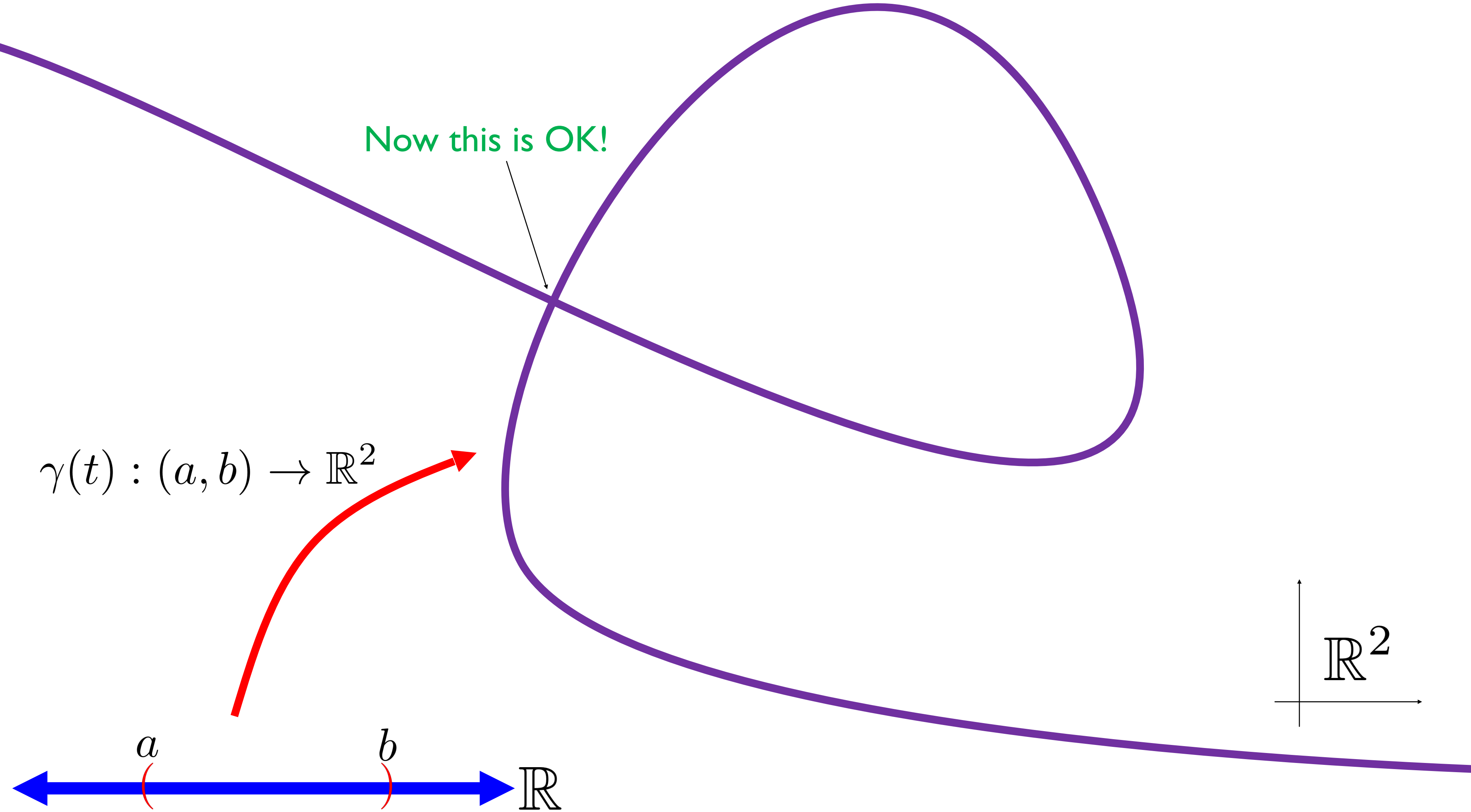
Geometric Definition

Set of points that locally looks like a line.

Differential Geometry Definition



Parameterized Curve



Some Vocabulary

- Trace of parameterized curve

$$\{\gamma(t) : t \in (a, b)\}$$

- Component functions

$$\gamma(t) = (x(t), y(t), z(t))$$

Change of Parameter

$$\bar{t} \mapsto \gamma(g(\bar{t})) = \gamma \circ g(\bar{t})$$

Geometric measurements should be

invariant

to changes of parameter.

Dependence of Velocity

$$\tilde{\gamma}(s) := \gamma(\phi(s))$$

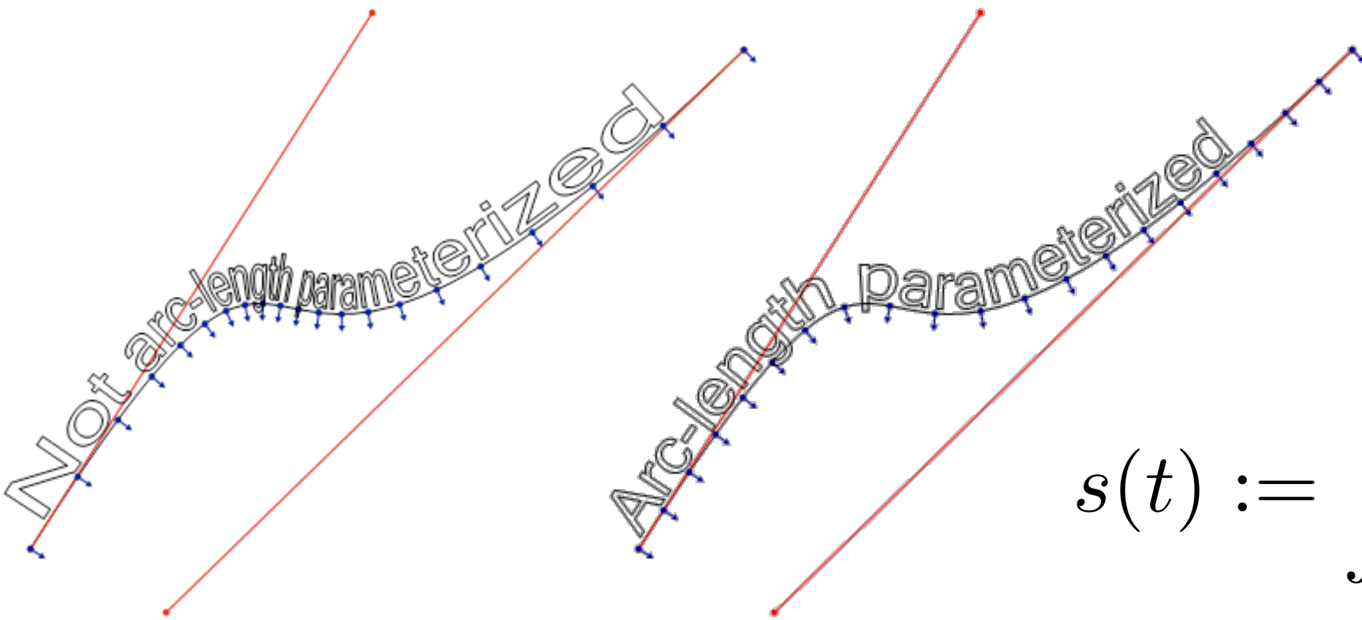
On the board:
Effect on velocity and acceleration.

Arc Length

$$\int_a^b \|\gamma'(t)\|\,dt$$

Parameterization by Arc Length

http://www.planetclegg.com/projects/WarpingTextToSplines.html



$$s(t) := \int_{t_0}^{t} \|\gamma'(t)\| \, dt$$

$$t(s) := \text{inverse of } s(t)$$

$$\bar{\gamma}(s) = \gamma(t(s))$$

Constant-speed parameterization

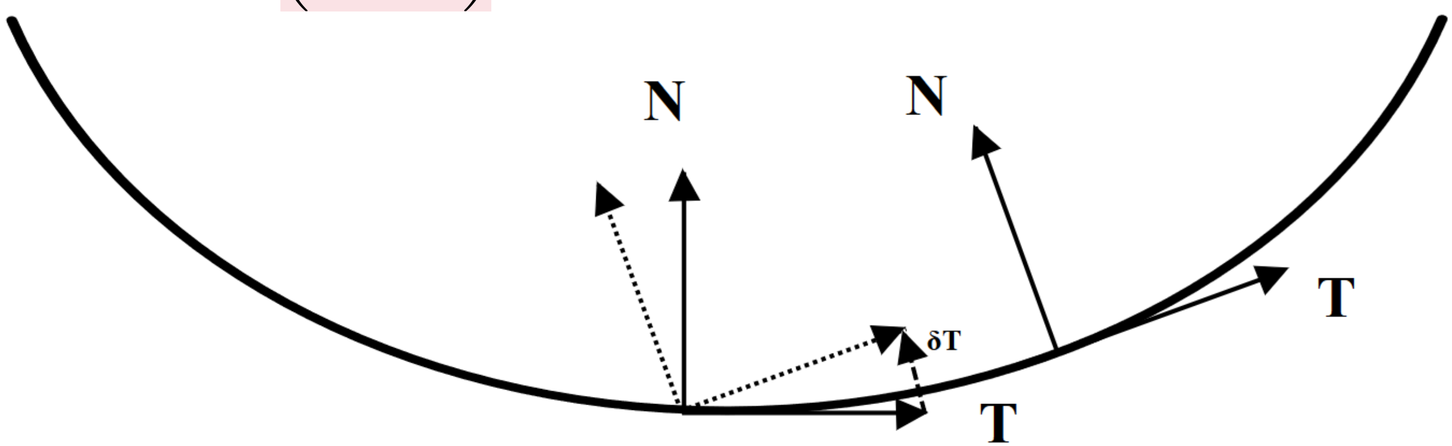
Moving Frame in 2D

$$T(s) := \gamma'(s)$$

$$\implies \quad \text{(on board) } \|T(s)\| \equiv 1$$

$$N(s) := JT(s)$$

$$\begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix}$$



https://en.wikipedia.org/wiki/Frenet%E2%80%93Serret_formulas

Philosophical Point

Differential geometry "should" be

coordinate-invariant.

Referring to x and y is a hack!

(but sometimes convenient…)

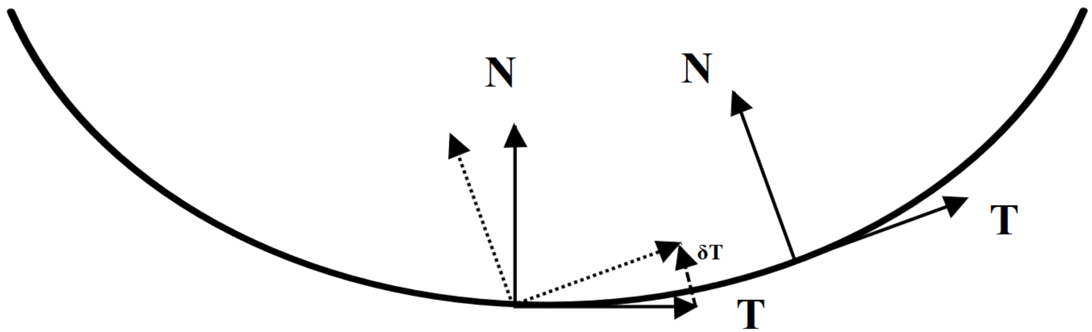
Q:

How do you characterize shape without coordinates?

Turtles All The Way Down

On the board:

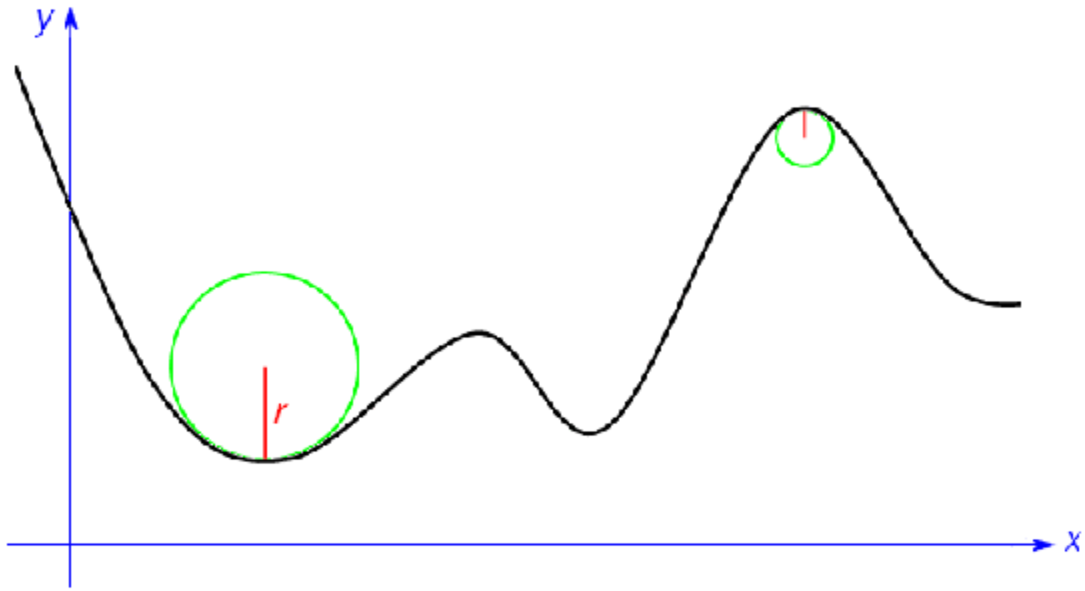
$$\frac{d}{ds}\begin{pmatrix} T(s) \\ N(s) \end{pmatrix} := \begin{pmatrix} 0 & k(s) \\ -k(s) & 0 \end{pmatrix}\begin{pmatrix} T(s) \\ N(s) \end{pmatrix}$$



https://en.wikipedia.org/wiki/Frenet%E2%80%93Serret_formulas

Use coordinates *from* the curve to express its shape!

Radius of Curvature



$$r(s) := \frac{1}{k(s)}$$

https://www.quora.com/What-is-the-base-difference-between-radius-of-curvature-and-radius-of-gyration

Fundamental theorem of the local theory of plane curves:

$k(s)$ characterizes a planar curve up to rigid motion.

Fundamental theorem of the local theory of plane curves:

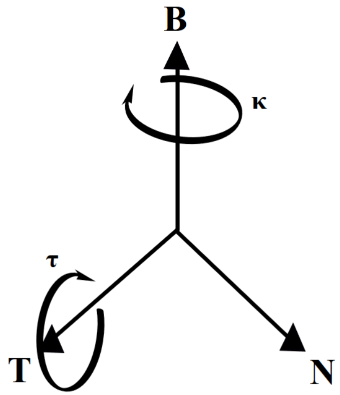
$k(s)$ characterizes a planar curve up to rigid motion.

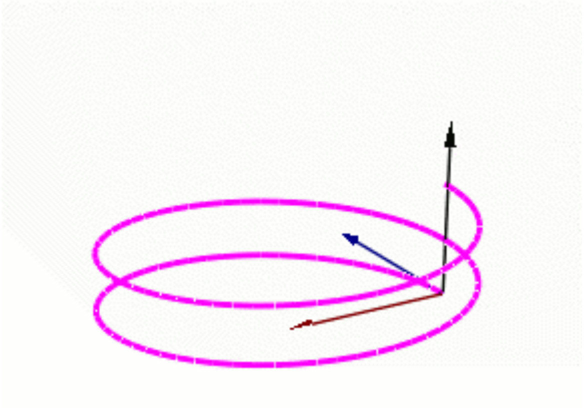
Statement shorter than the name!

Frenet Frame: Curves in

- Binormal:
- Curvature: In-plane motion
- Torsion: Out-of-plane motion

$$\frac{d}{ds}\begin{pmatrix} T \\ N \\ B \end{pmatrix} = \begin{pmatrix} 0 & \kappa & 0 \\ -\kappa & 0 & \tau \\ 0 & -\tau & 0 \end{pmatrix}\begin{pmatrix} T \\ N \\ B \end{pmatrix}$$





Fundamental theorem of the local theory of space curves:

Curvature and torsion characterize a 3D curve up to rigid motion.

Aside: Generalized Frenet Frame

$$\gamma(s) : \mathbb{R} \to \mathbb{R}^n$$

$$\frac{d}{ds}\begin{pmatrix} e_1(s) \\ e_2(s) \\ \vdots \\ e_n(s) \end{pmatrix} = \begin{pmatrix} 0 & \chi_1(s) & & 0 \\ -\chi_1(s) & \ddots & \ddots & \\ & \ddots & 0 & \chi_{n-1}(s) \\ 0 & & -\chi_{n-1}(s) & 0 \end{pmatrix} \begin{pmatrix} e_1(s) \\ e_2(s) \\ \vdots \\ e_n(s) \end{pmatrix}$$

Suspicion: Application to time series analysis? ML?

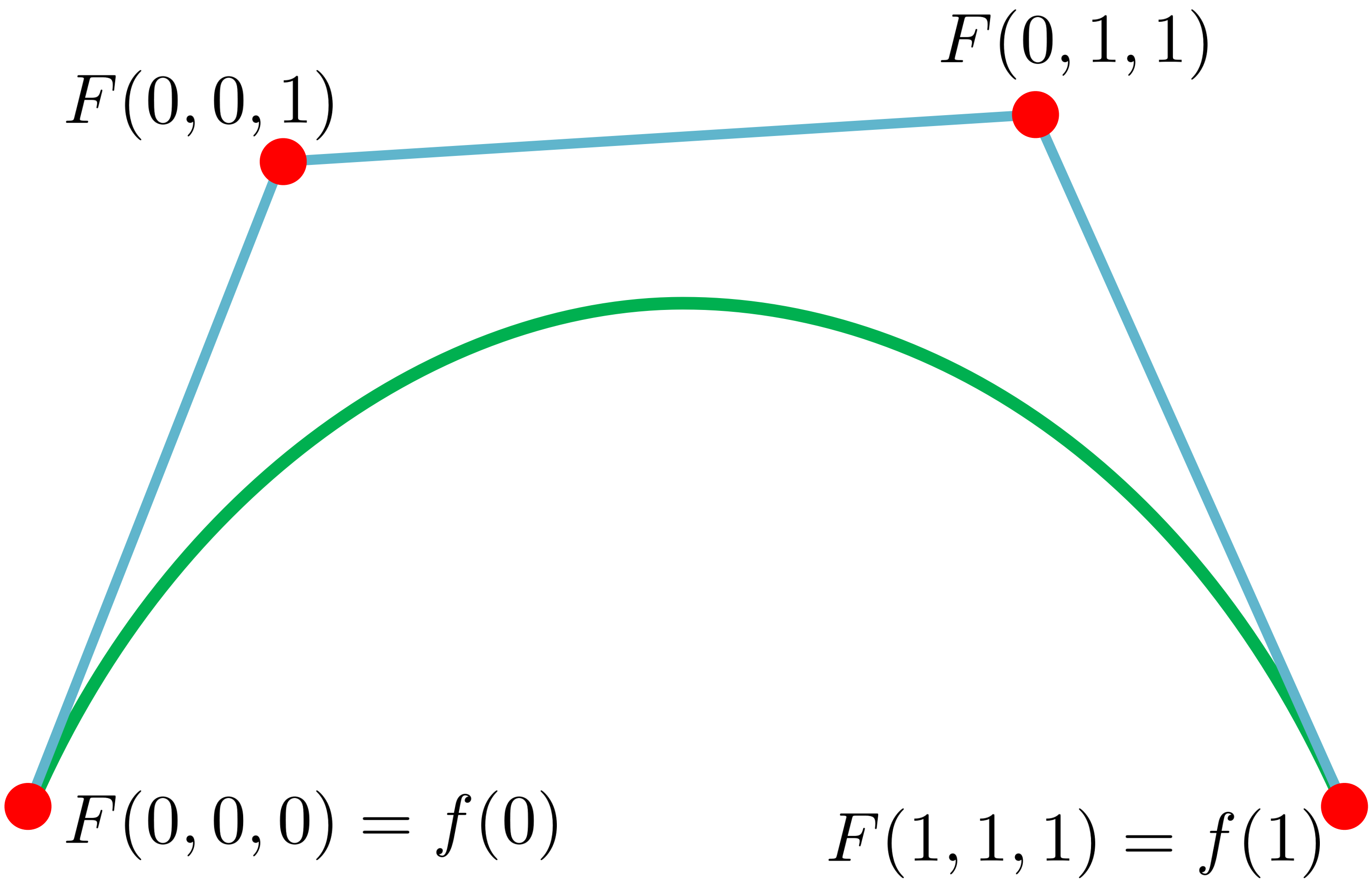
C. Jordan, 1874

Gram-Schmidt on first *n* derivatives

Q:

What do these calculations look like in software?

Old-School Approach



Piecewise smooth approximations

Question

What is the arc length of a cubic Bézier curve?

$$\int_a^b \|\gamma'(t)\| \, dt$$

Question

What is the arc length of a cubic Bézier curve?

$$\int_a^b \|\gamma'(t)\| \, dt$$

Not known in closed form.

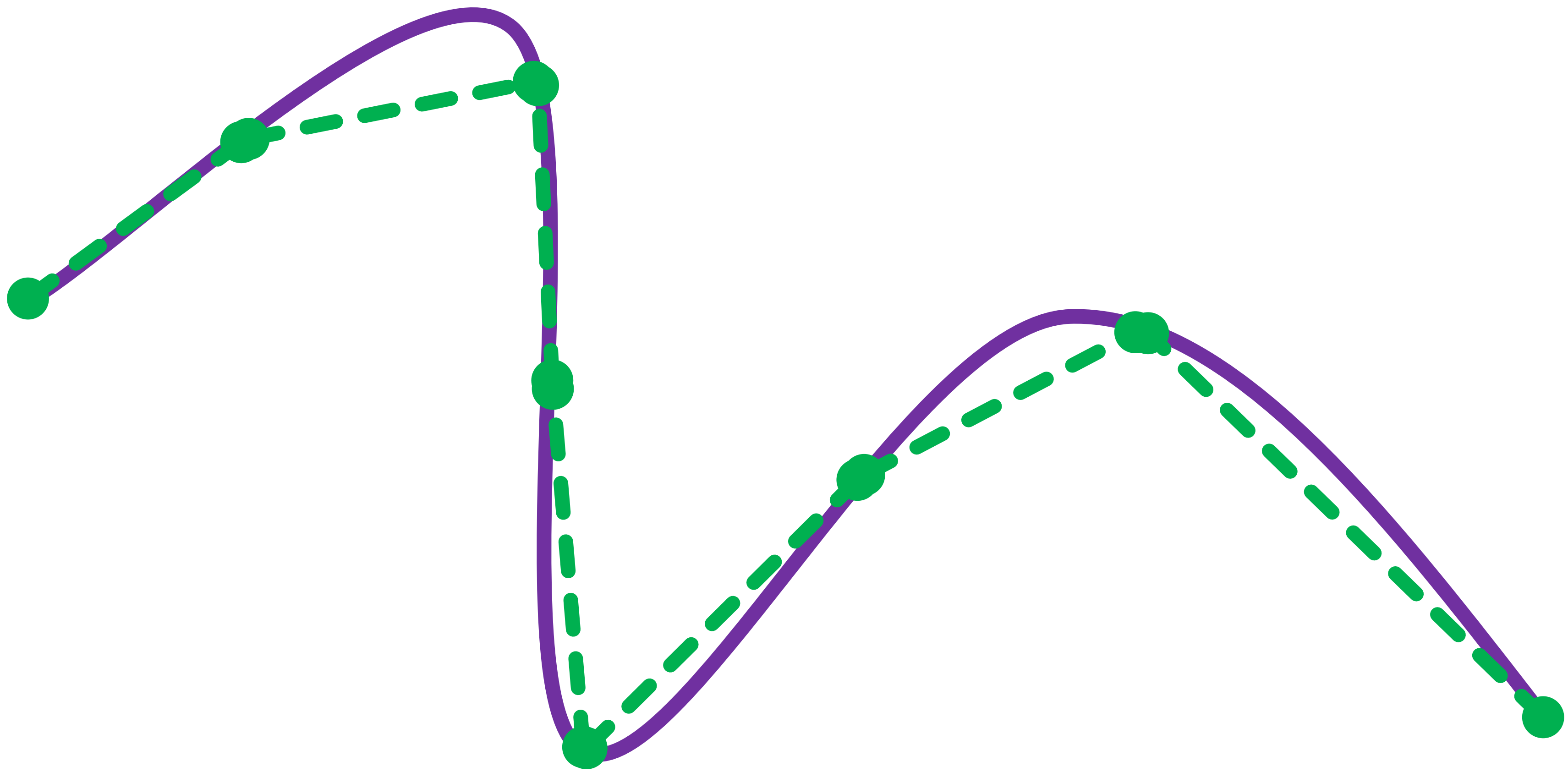
Sad fact:

Closed-form expressions rarely exist. When they do exist, they usually are messy.

Only Approximations Anyway

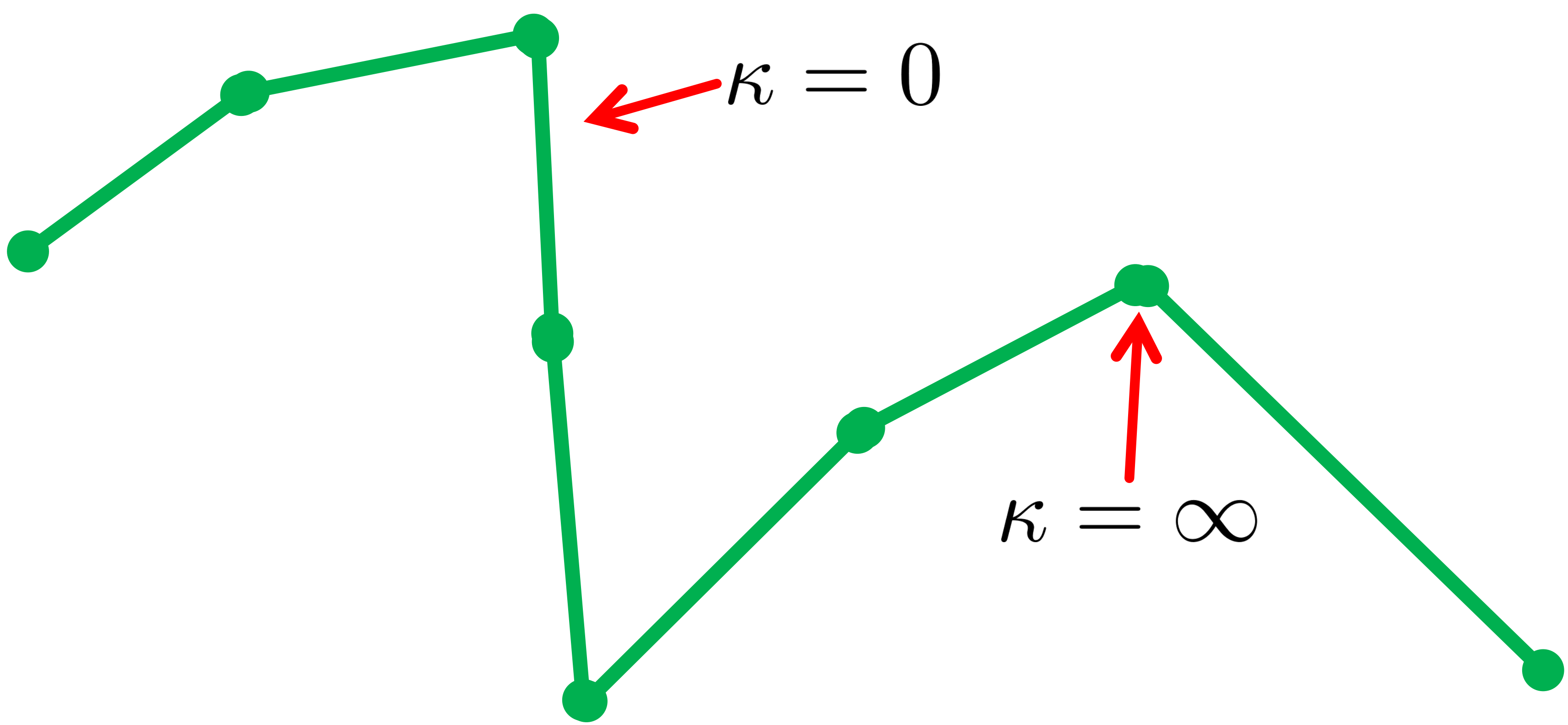
$$\{\text{Bézier curves}\} \subsetneq \{\gamma : \mathbb{R} \to \mathbb{R}^3\}$$

Equally Reasonable Approximation



Piecewise linear

Big Problem



Boring differential structure

Finite Difference Approach

$$f'(x) \approx \frac{1}{h}[f(x+h) - f(x)]$$

THEOREM: As , [insert statement].

Reality Check

$$f'(x) \approx \frac{1}{h}[f(x+h) - f(x)]$$

THEO

$$\boxed{h > 0}$$

ment].

Two Key Considerations

- Convergence to continuous theory
- Discrete behavior

Goal

Examine discrete theories of differentiable curves.

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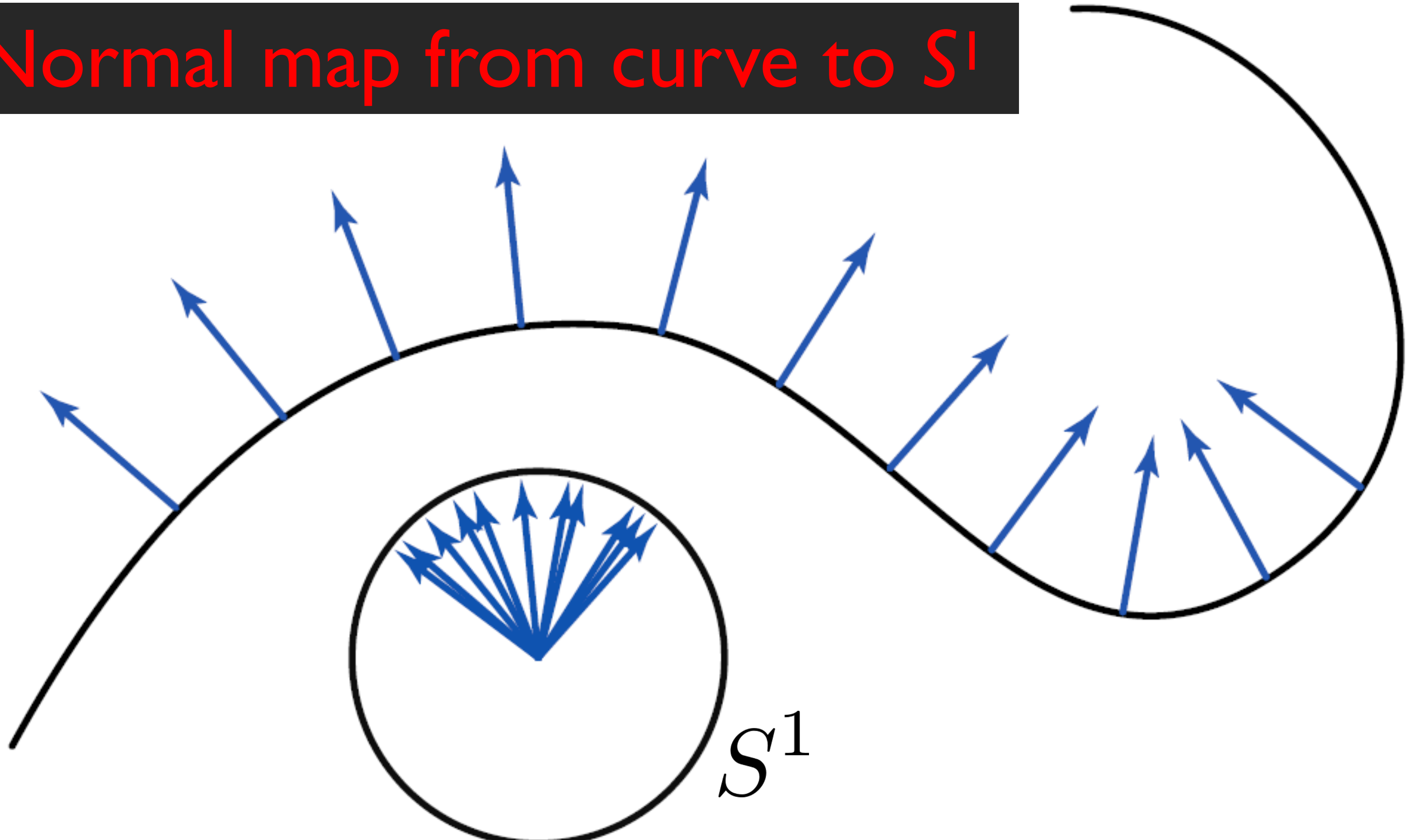
Examine discrete theor<u>ies</u> of differentiable curves.

Gauss Map

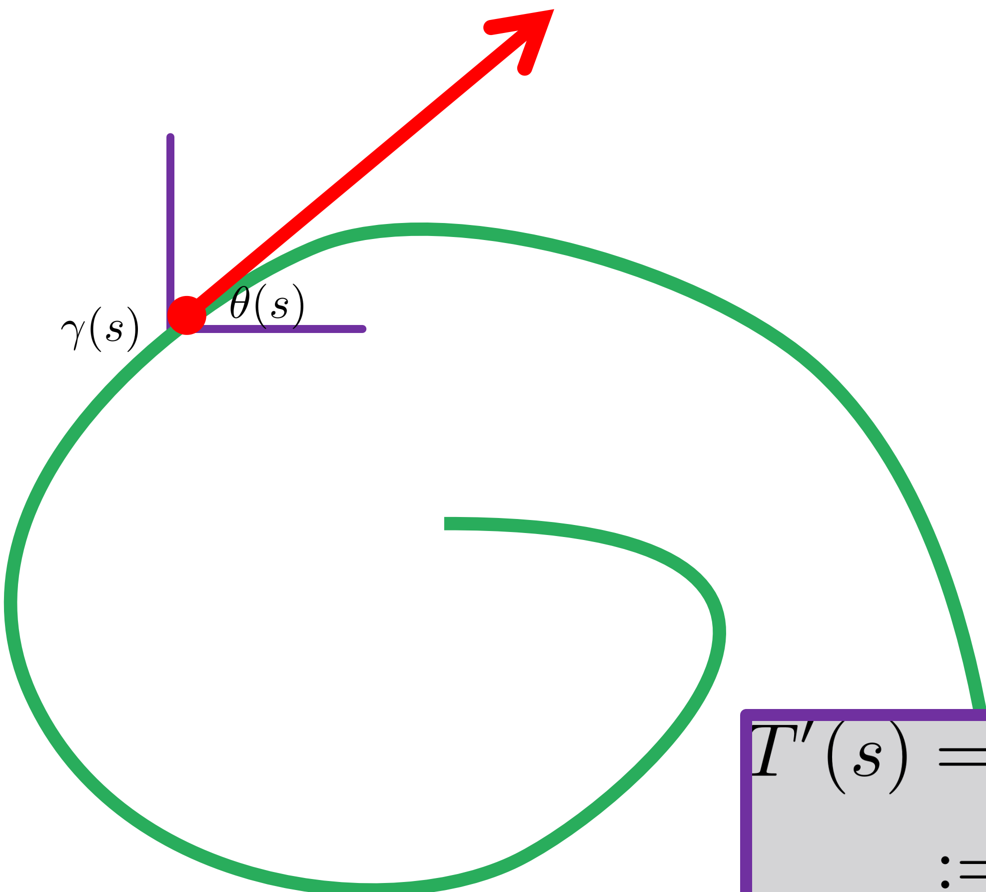
Normal map from curve to S^1



http://mesh.brown.edu/3DPGP-2007/pdfs/sg06-course01.pdf

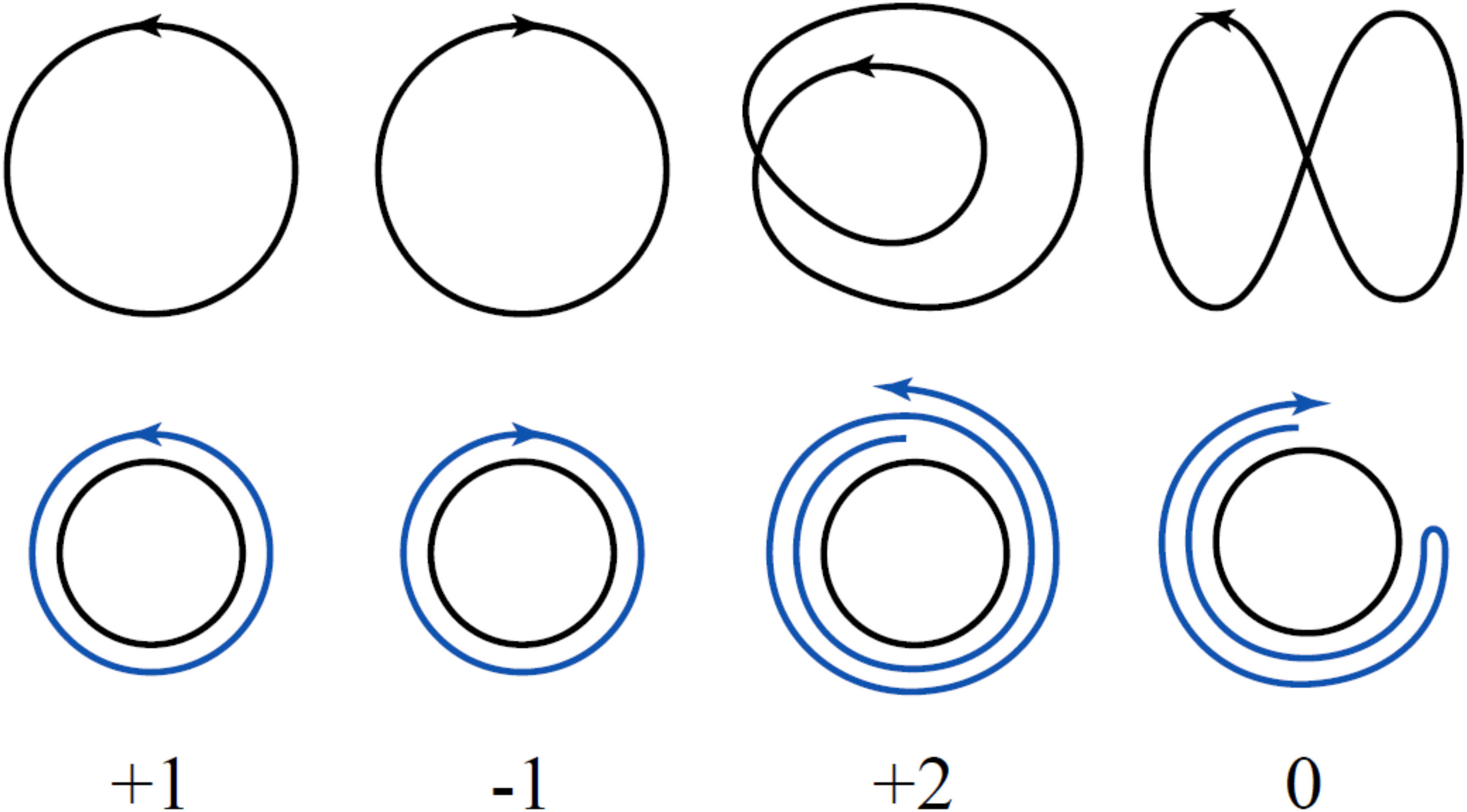
Signed Curvature on Plane Curves

$$T(s) = (\cos\theta(s), \sin\theta(s))$$



$$\boxed{\begin{aligned} T'(s) &= \theta'(s)(-\sin\theta(s), \cos\theta(s)) \\ &:= \kappa(s)N(s) \end{aligned}}$$

Turning Numbers



http://mesh.brown.edu/3DPGP-2007/pdfs/sg06-course01.pdf

Recovering Theta

$$\theta'(s) = \kappa(s)$$

$$\Downarrow$$

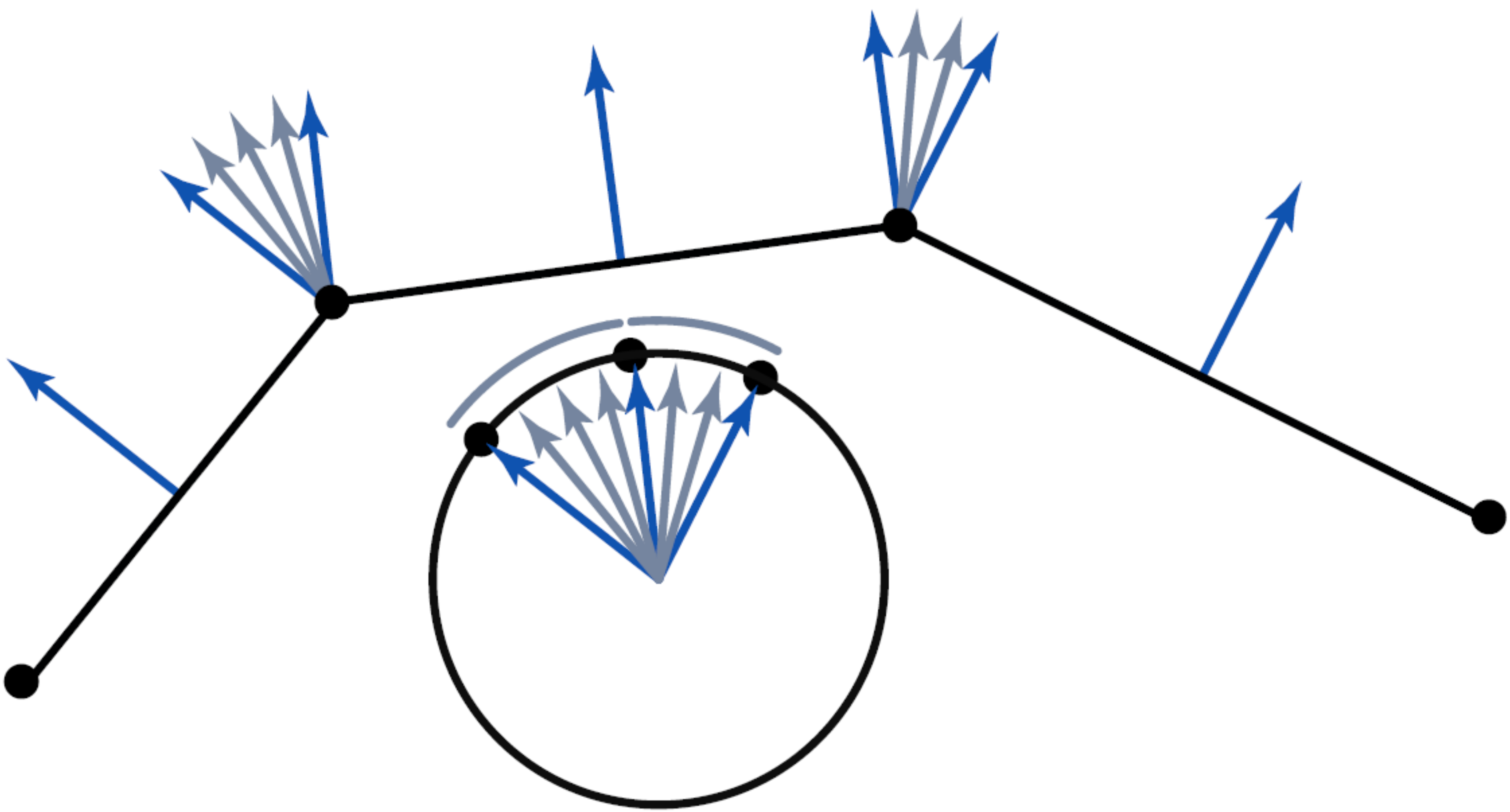
$$\Delta\theta = \int_{s_0}^{s_1} \kappa(s)\, ds$$

Turning Number Theorem

$$\boxed{\int_{\Omega} \kappa(s)\, ds = 2\pi k}$$

A "global" theorem!

Discrete Gauss Map



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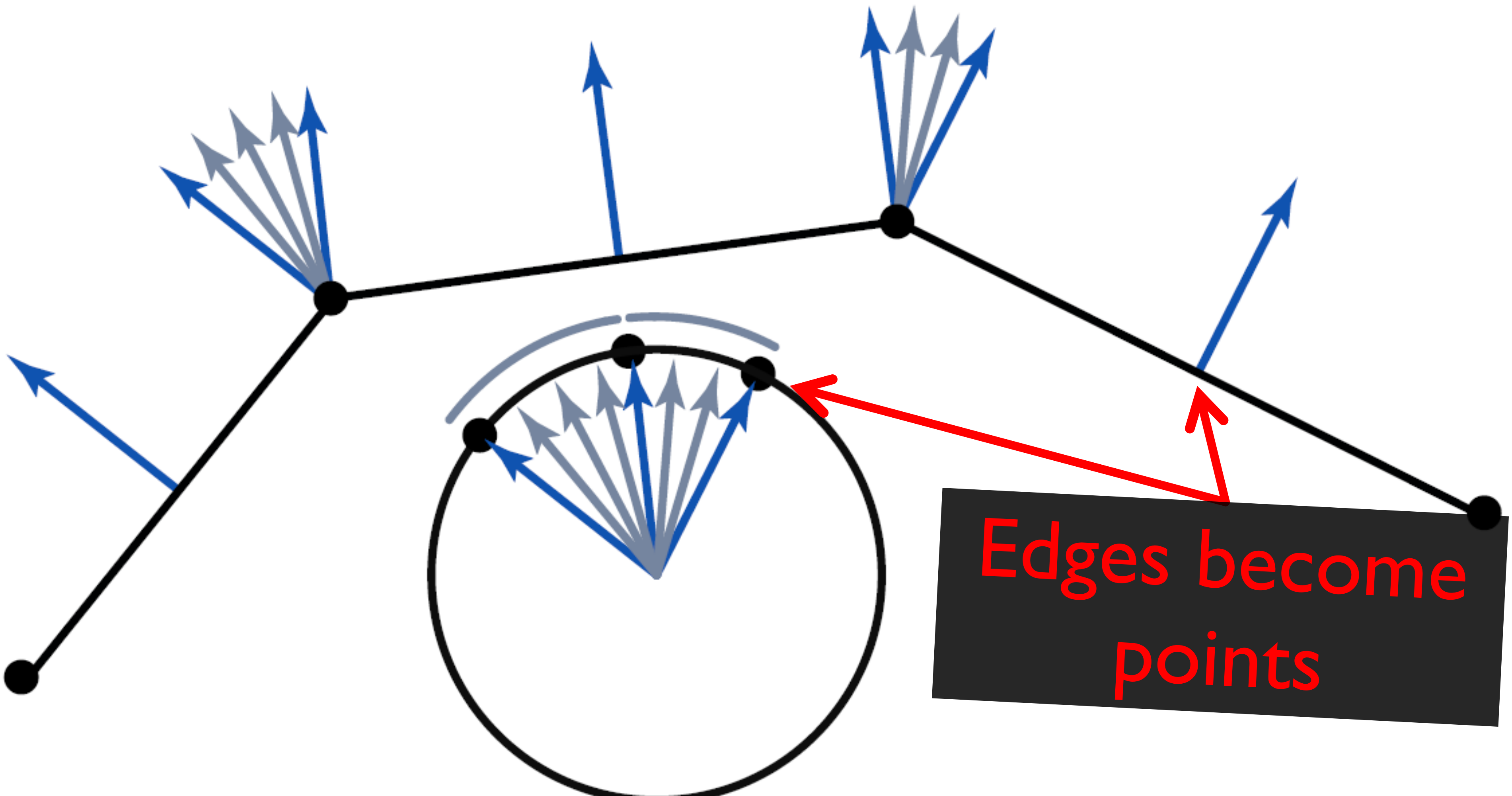
Discrete Gauss Map



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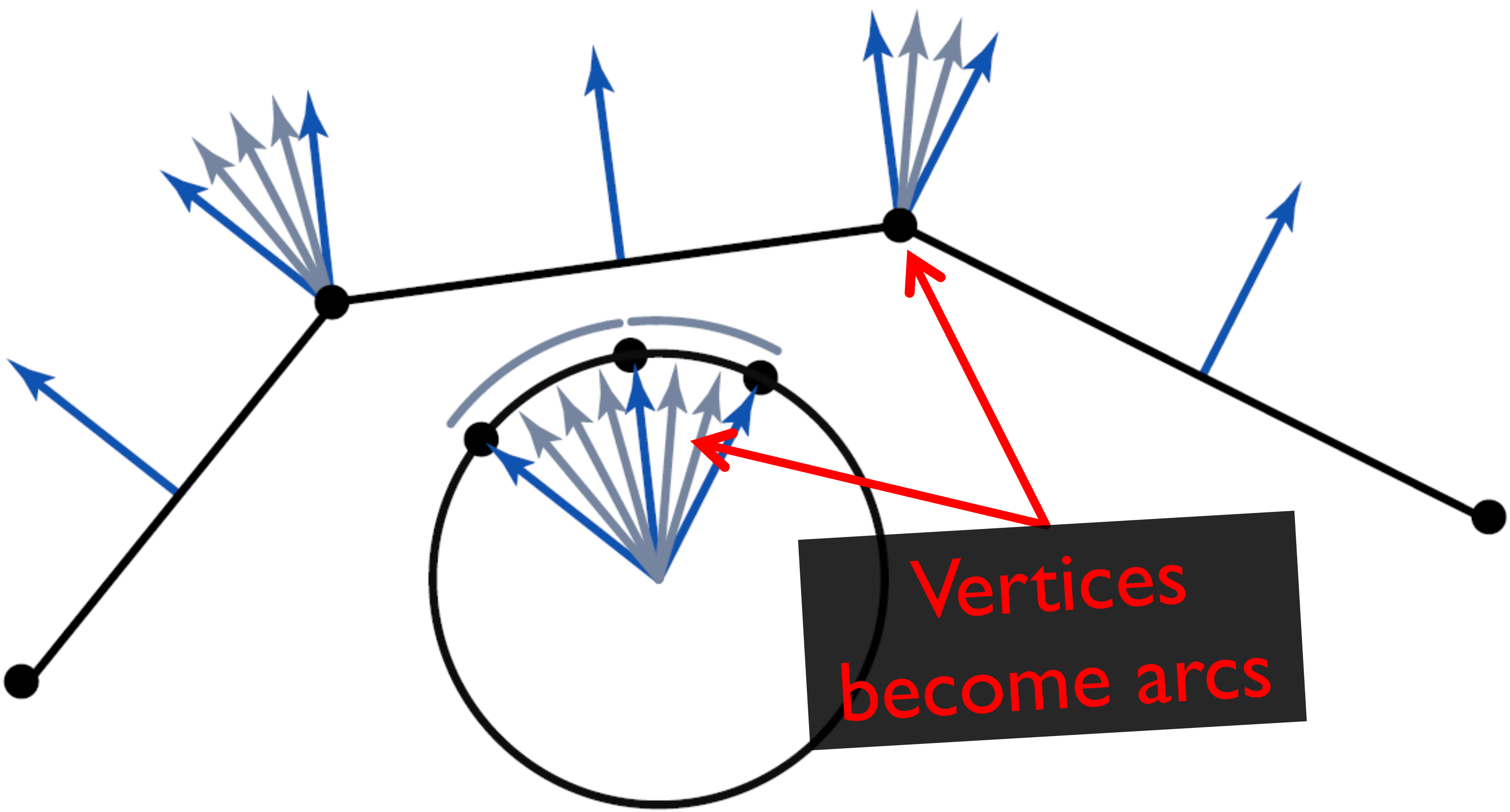
Discrete Gauss Map



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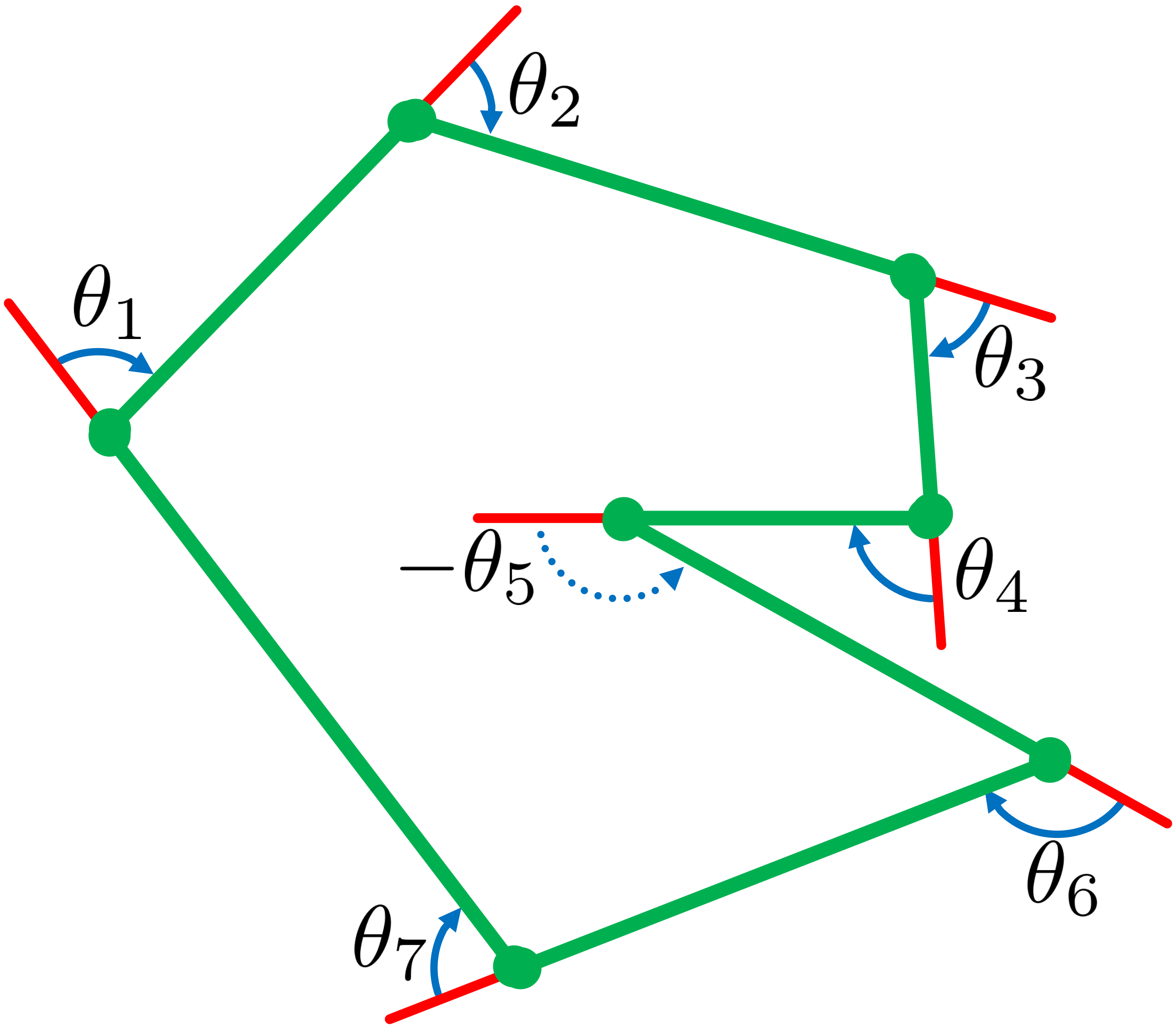
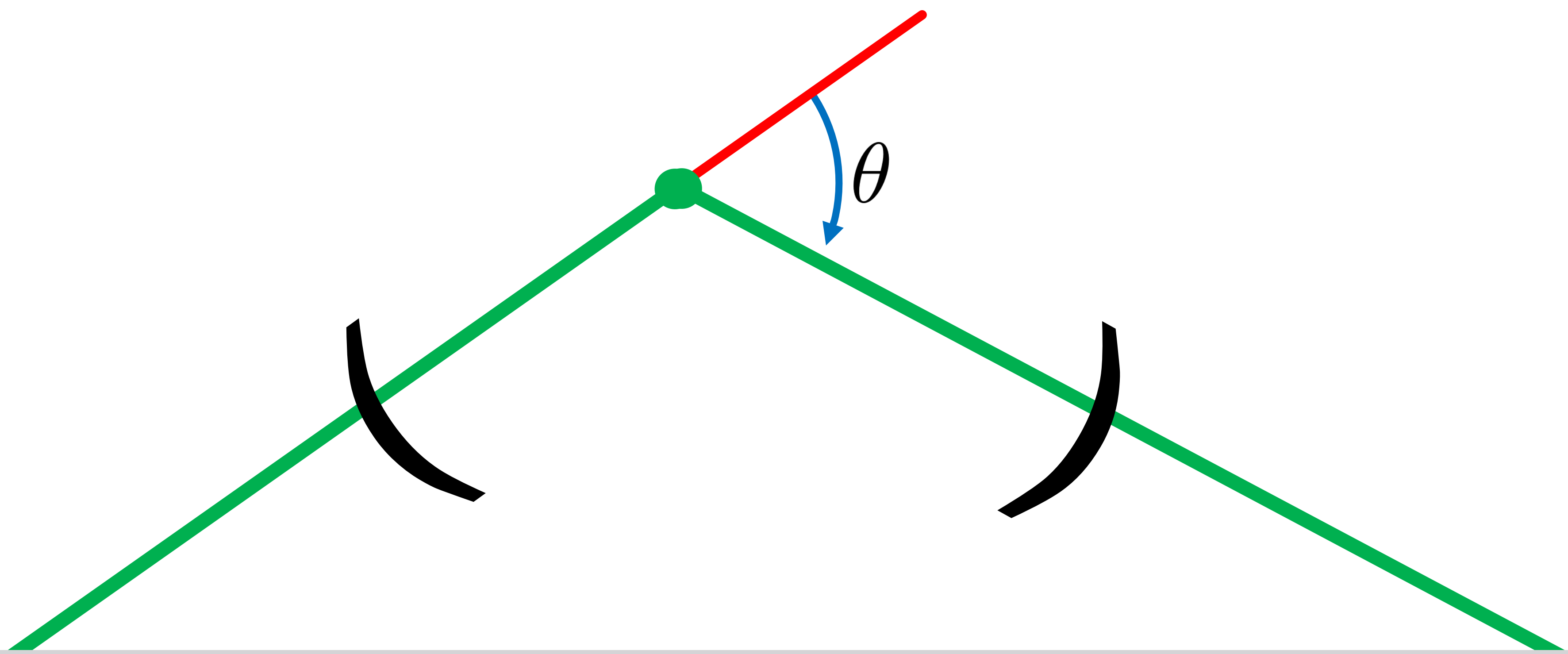
Key Observation



$$\sum_i \theta_i = 2\pi k$$

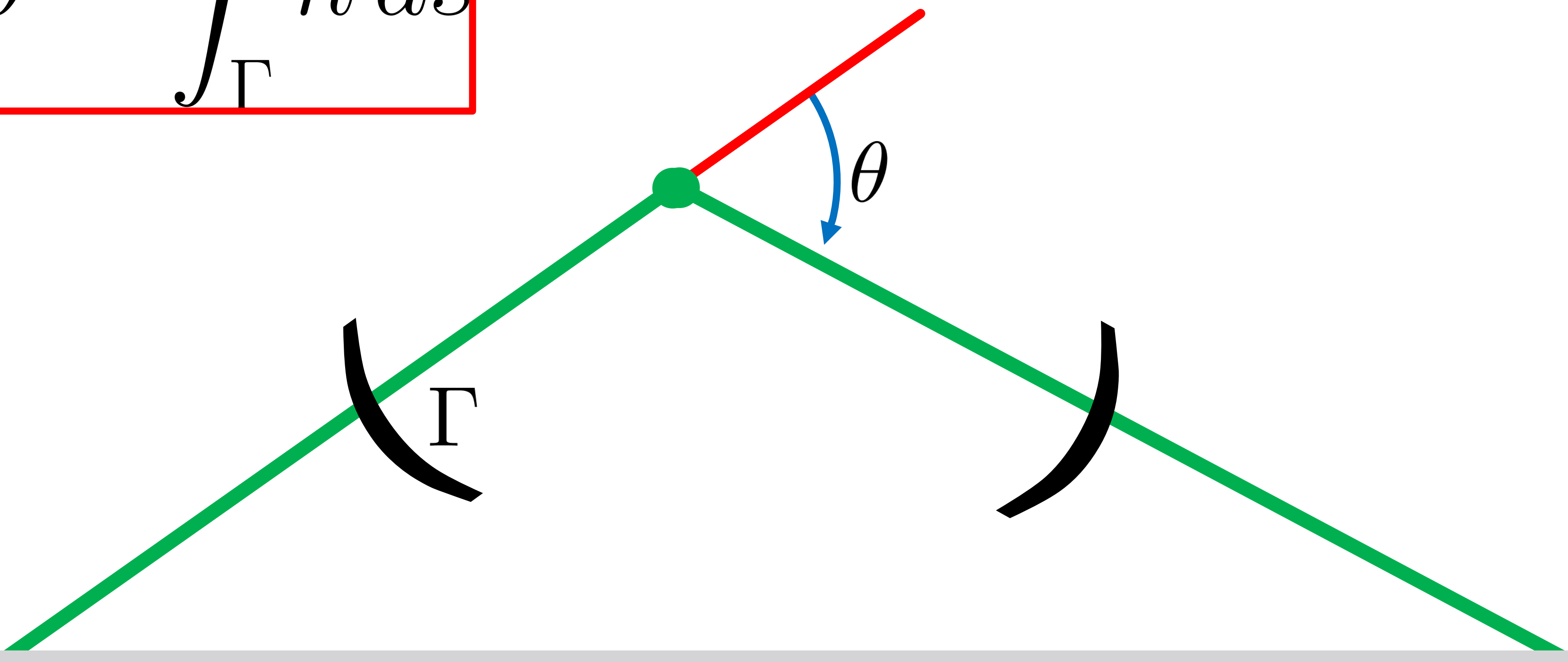
What's Going On?



Total change in curvature

What's Going On?

$$\boxed{\theta = \int_\Gamma \kappa \, ds}$$

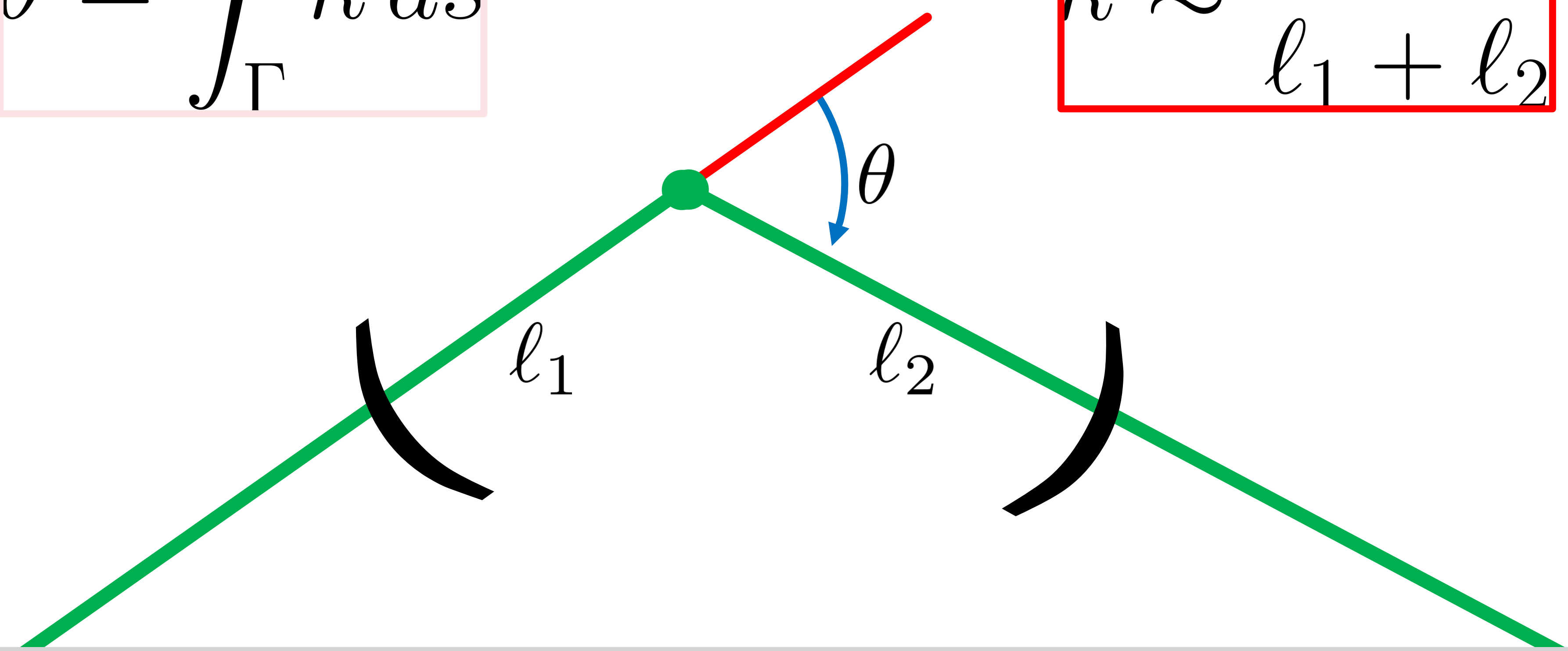


Total change in curvature

What's Going On?

$$\theta = \int_\Gamma \kappa \, ds$$

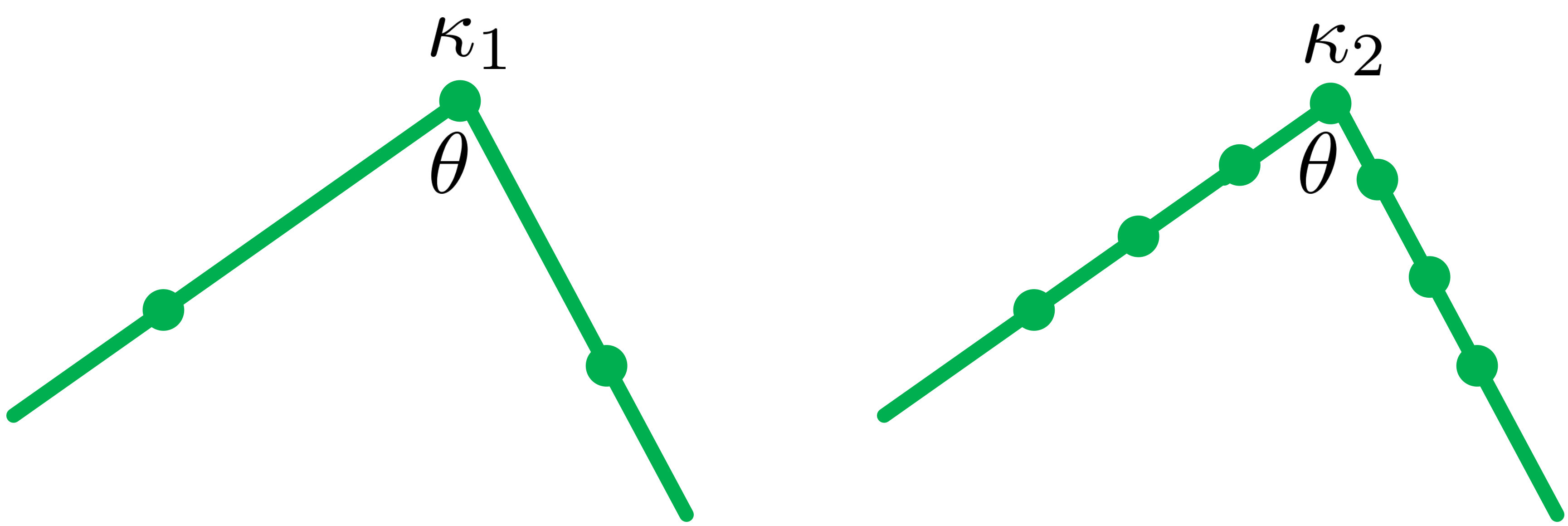
$$\kappa \approx \frac{\theta}{\ell_1 + \ell_2}$$



Total change in curvature

Interesting Distinction

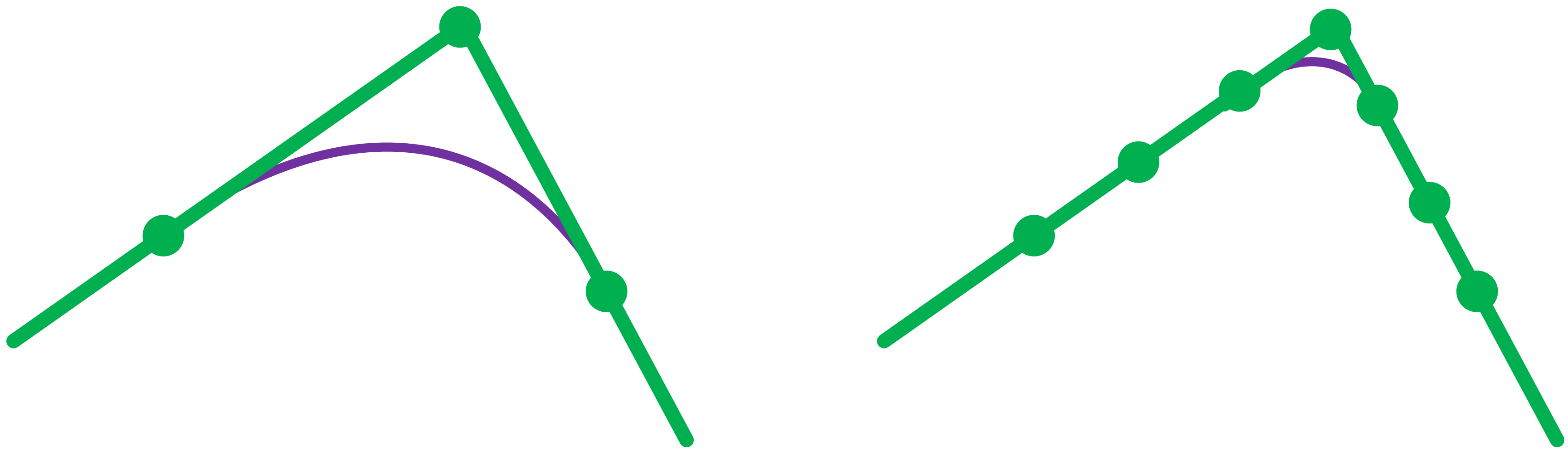
$$\kappa_1 \neq \kappa_2$$



Same integrated curvature

Interesting Distinction

$$\kappa_1 \neq \kappa_2$$



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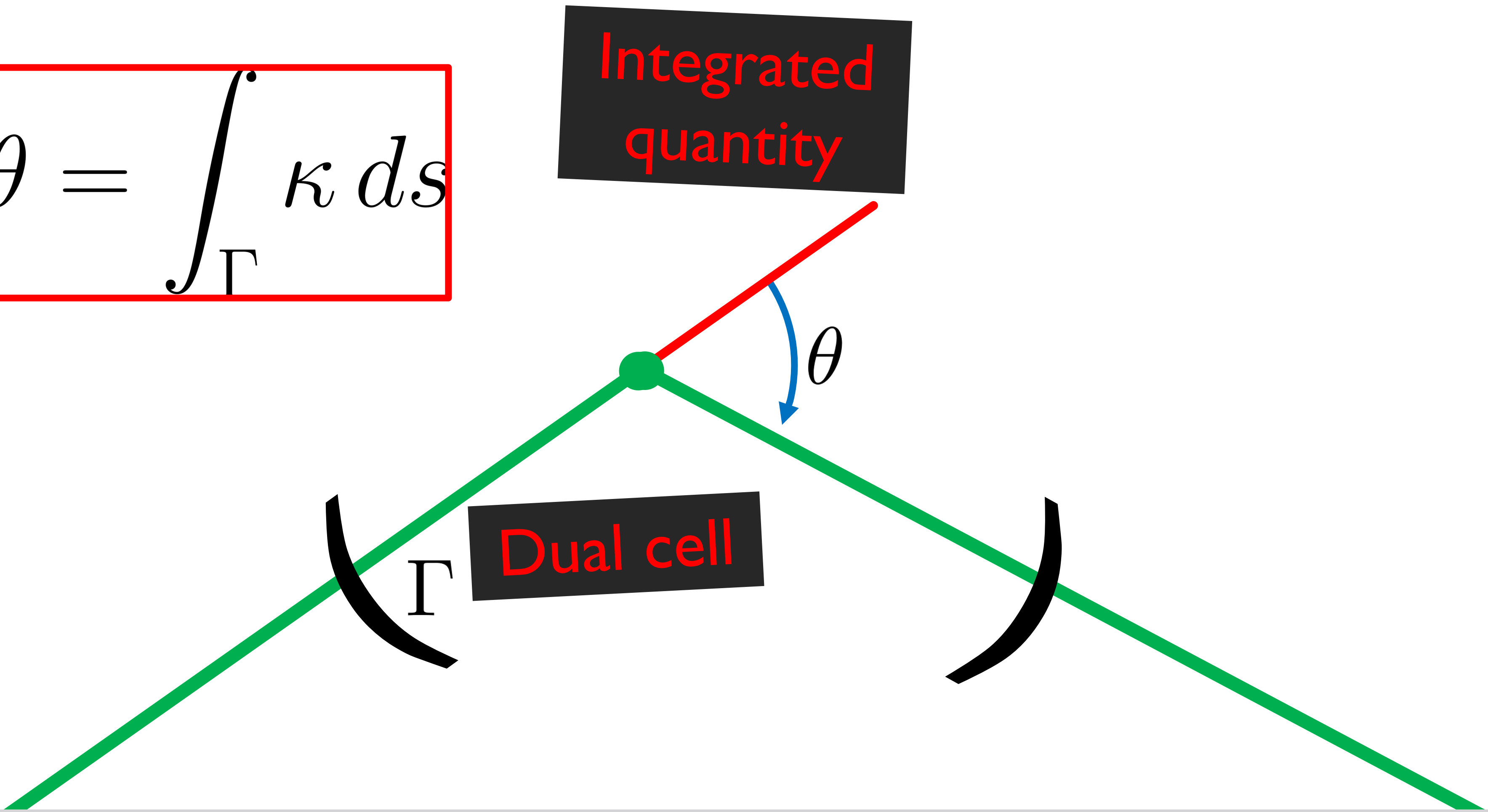
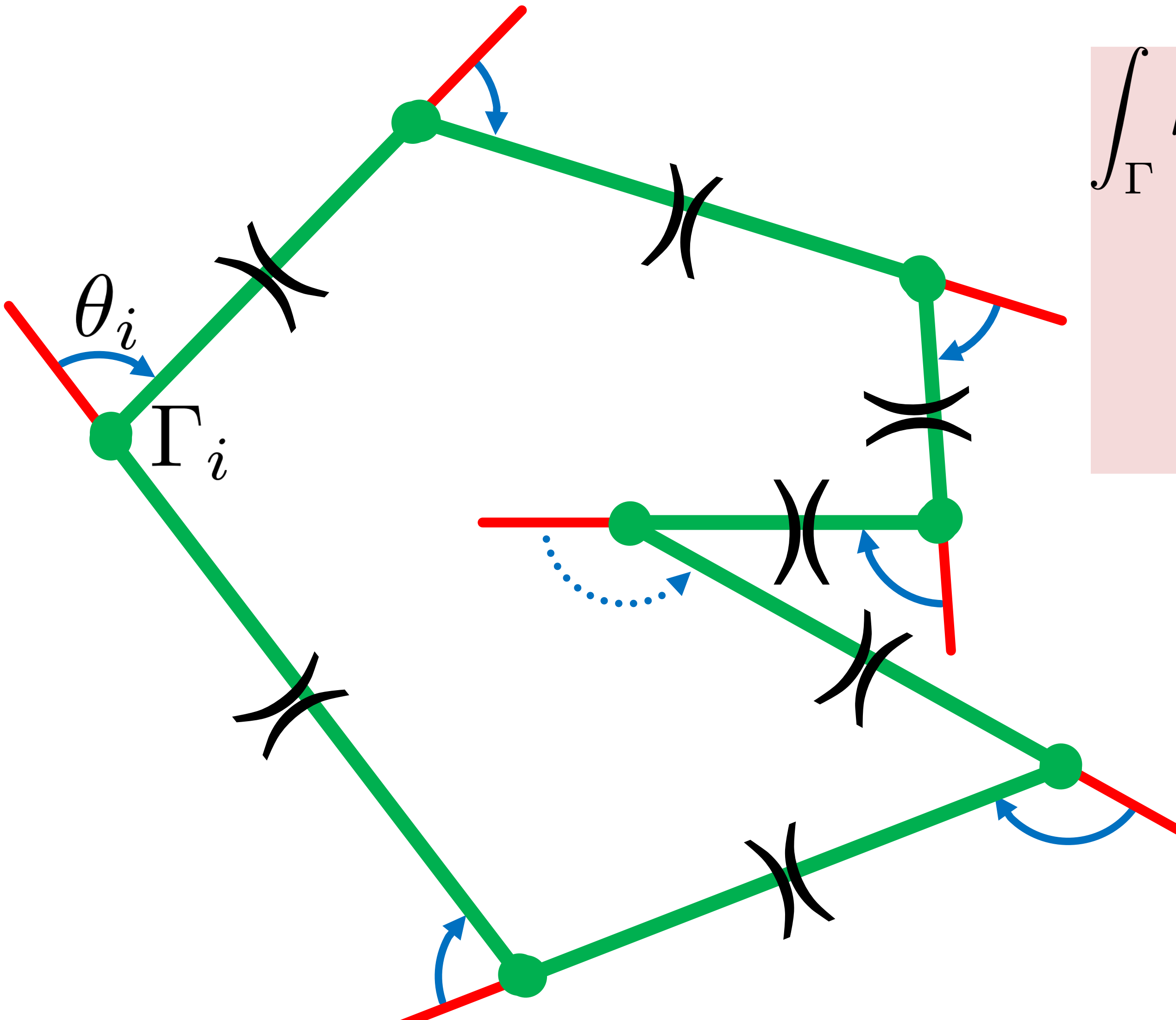
What's Going On?

$$\boxed{\theta = \int_\Gamma \kappa \, ds}$$



Total change in curvature

Discrete Turning Angle Theorem

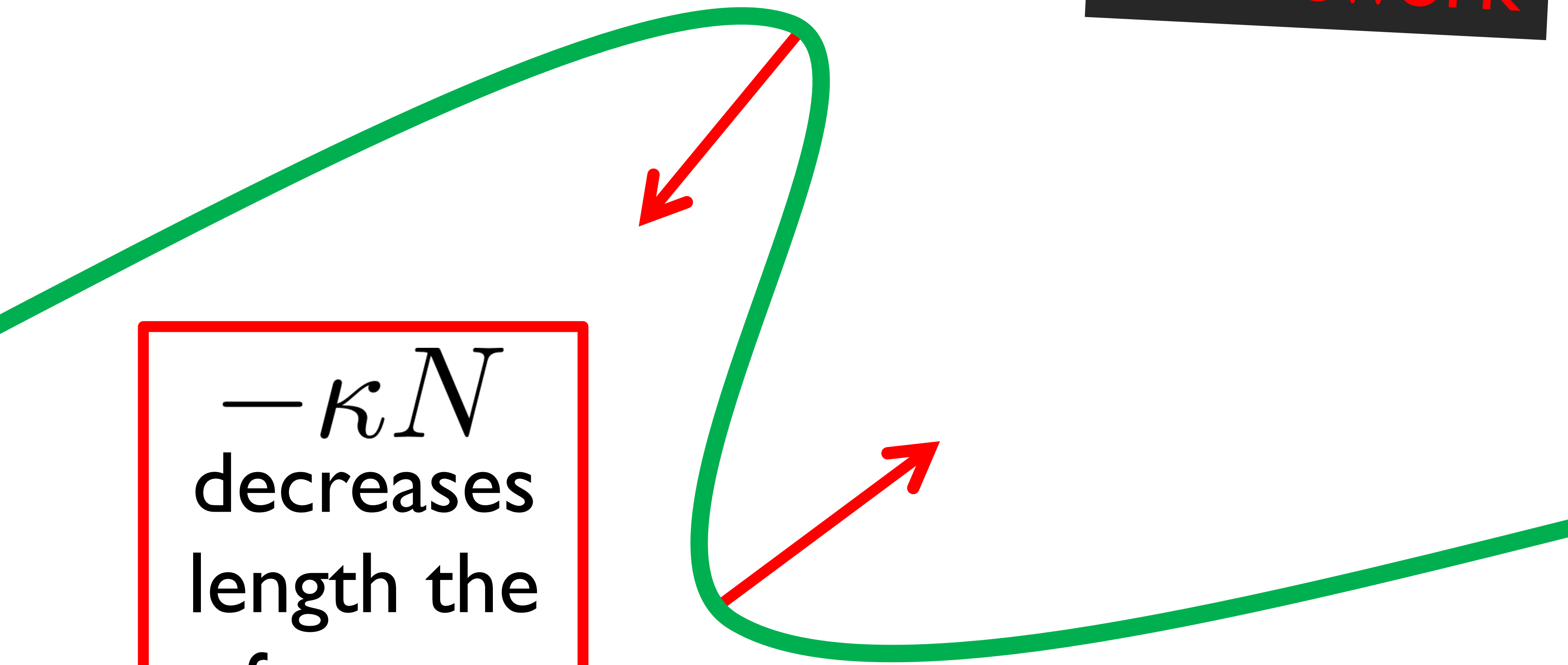


$$\int_\Gamma \kappa\, ds = \sum_i \int_{\Gamma_i} \kappa\, ds$$
$$= \sum_i \theta_i$$
$$= 2\pi k$$

Preserved structure!

Alternative Definition

Homework



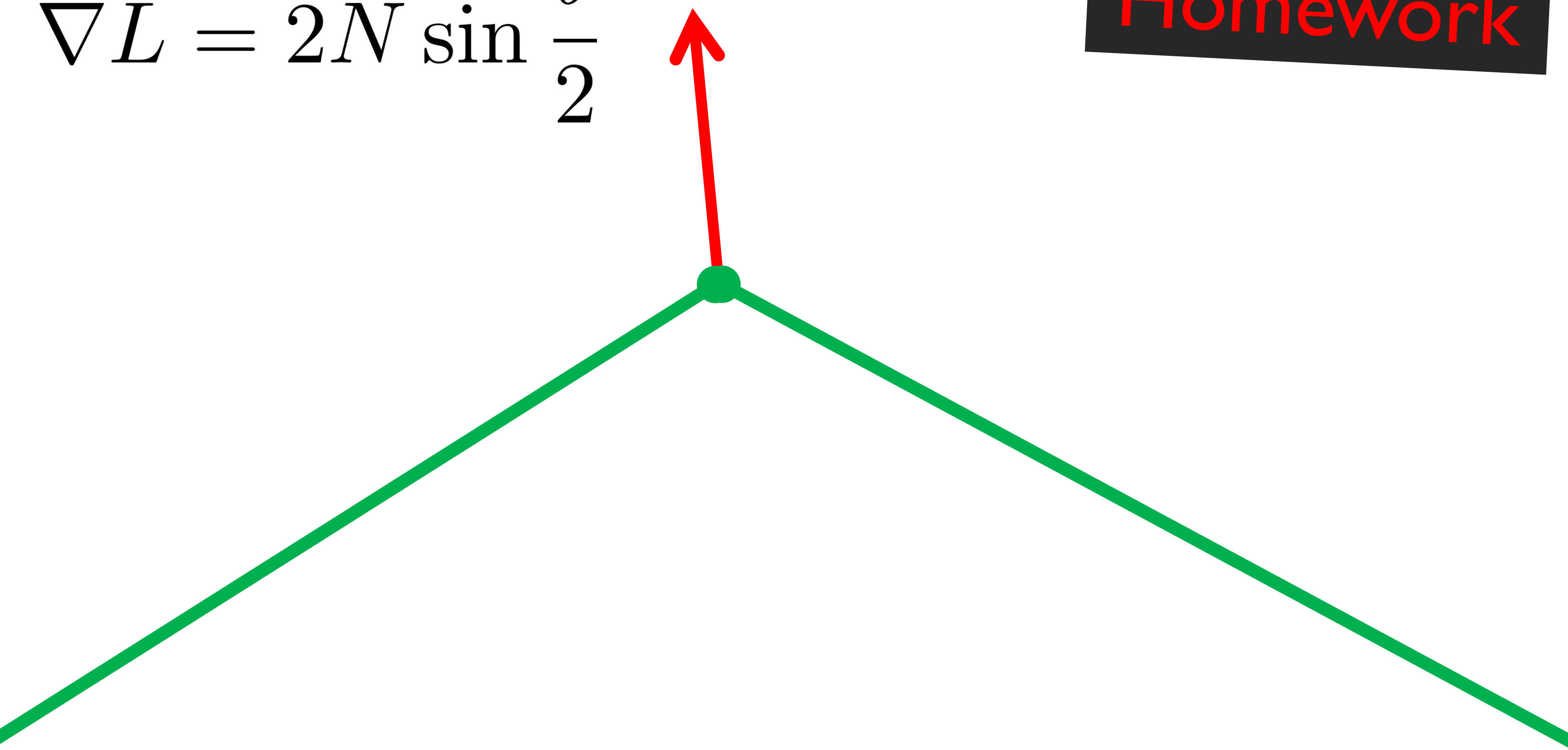
$$-\kappa N$$

decreases length the fastest.

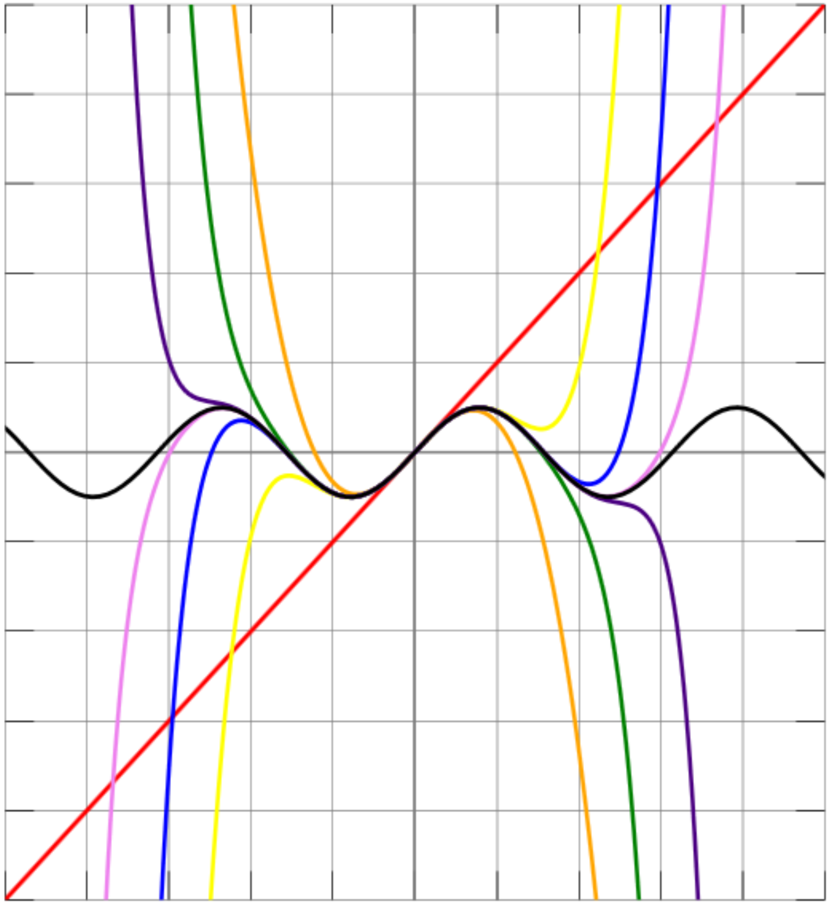
Discrete Case

$$\nabla L = 2N \sin \frac{\theta}{2}$$

Homework



For Small



http://en.wikipedia.org/wiki/Taylor_series

$$2\sin\frac{\theta}{2} \approx 2\cdot\frac{\theta}{2}$$

$$= \theta$$

Same behavior in the limit

Remaining Question

Does discrete curvature converge in limit?

Yes!

Remaining Question

Questions:

- Type of convergence?
- Sampling?
- Class of curves?

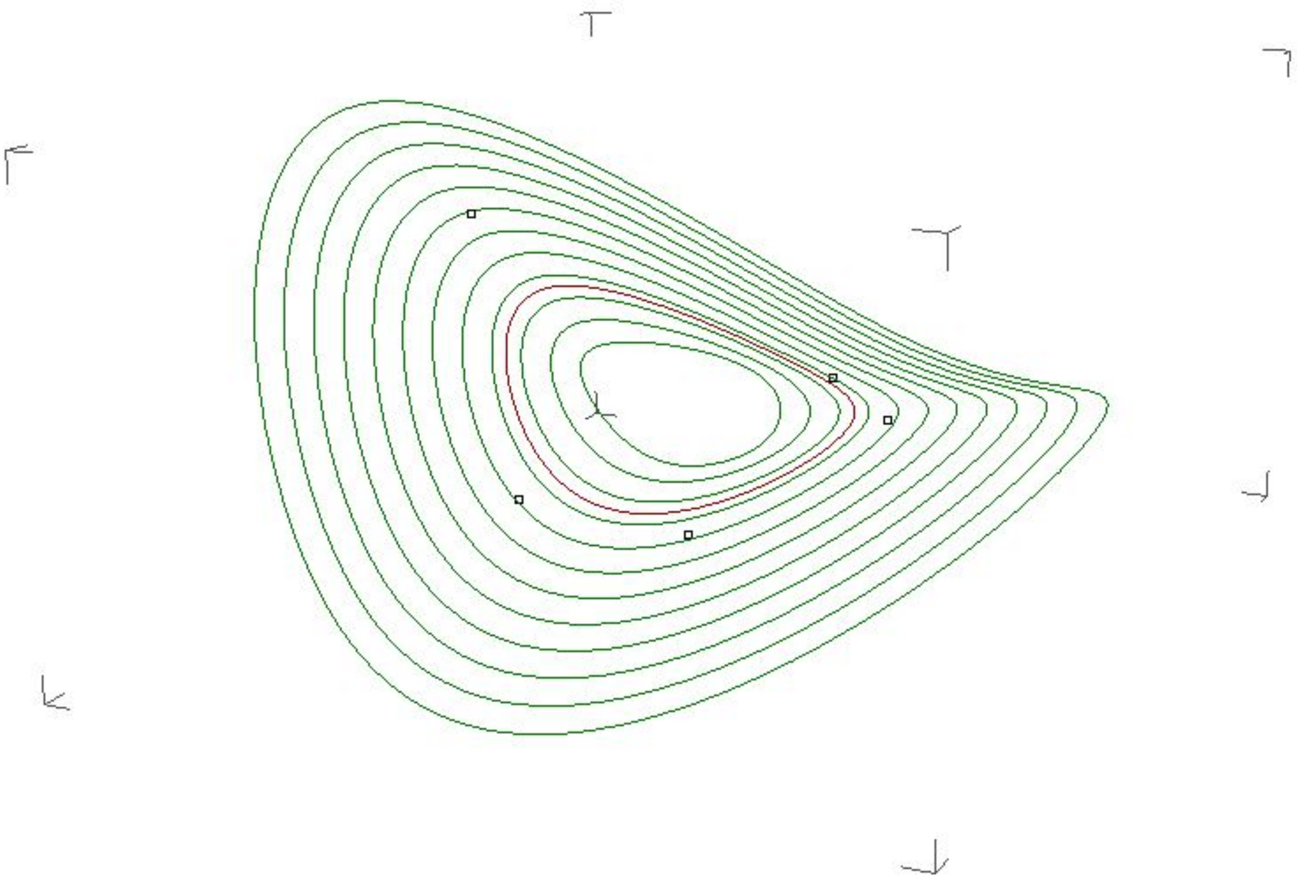
Does discrete curvature converge in limit?

Yes!

Discrete Differential Geometry

- Different discrete behavior
- Same convergence

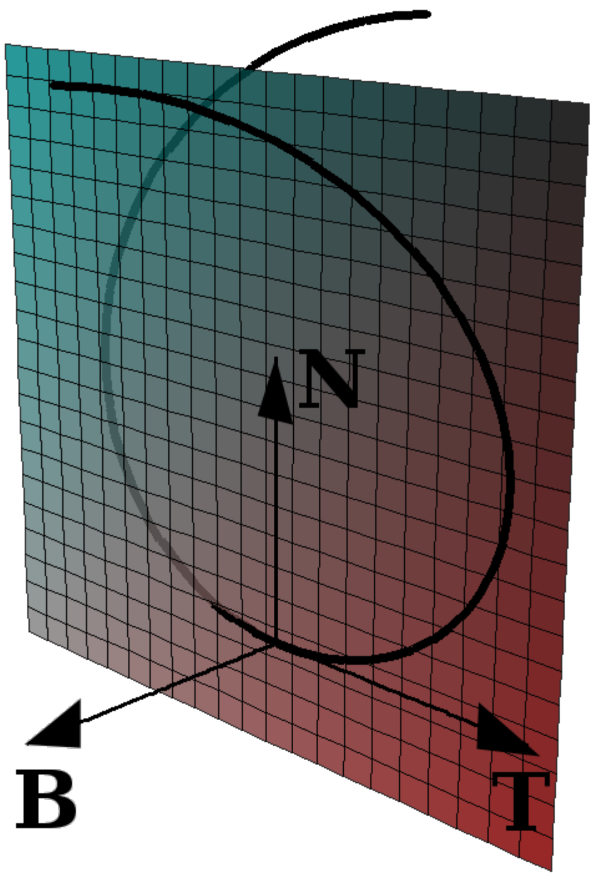
Next



http://www.grasshopper3d.com/forum/topics/offseting-3d-curves-component

Curves in 3D

Frenet Frame

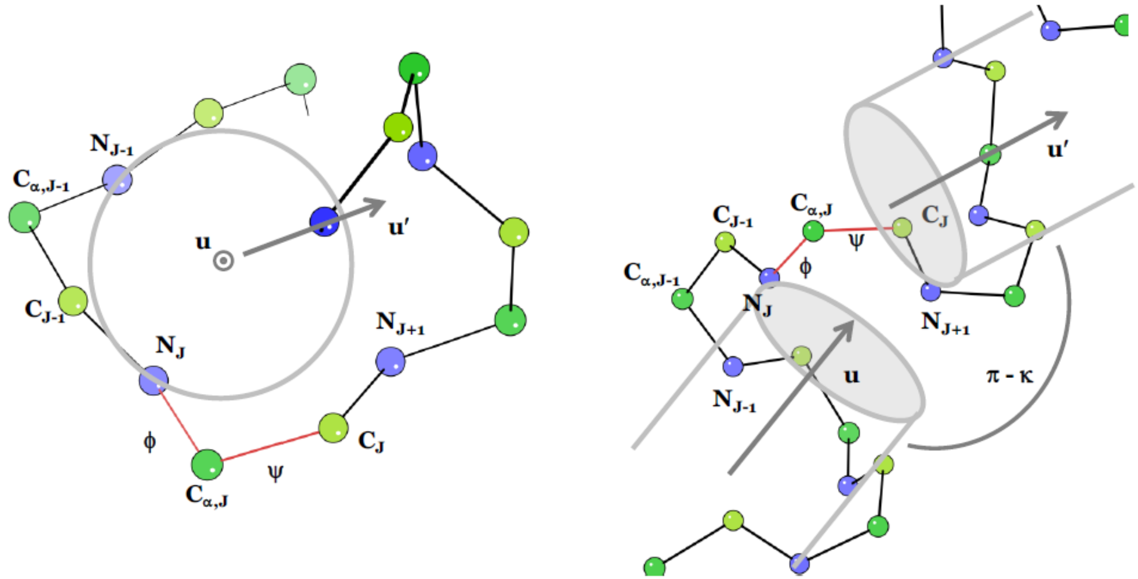


$$\frac{d}{ds}\begin{pmatrix} T \\ N \\ B \end{pmatrix} = \begin{pmatrix} 0 & \kappa & 0 \\ -\kappa & 0 & \tau \\ 0 & -\tau & 0 \end{pmatrix}\begin{pmatrix} T \\ N \\ B \end{pmatrix}$$

http://upload.wikimedia.org/wikipedia/commons/6/6f/Frenet.png

Application

NMR scanner



Kinked alpha helix

Structure Determination of Membrane Proteins Using Discrete Frenet Frame and Solid State NMR Restraints

Achuthan and Quine

Discrete Mathematics and its Applications, ed. M. Sethumadhavan (2006)

Potential Discretization

$$T_j = \frac{p_{j+1} - p_j}{\|p_{j+1} - p_j\|}$$

$$B_j = t_{j-1} \times t_j$$

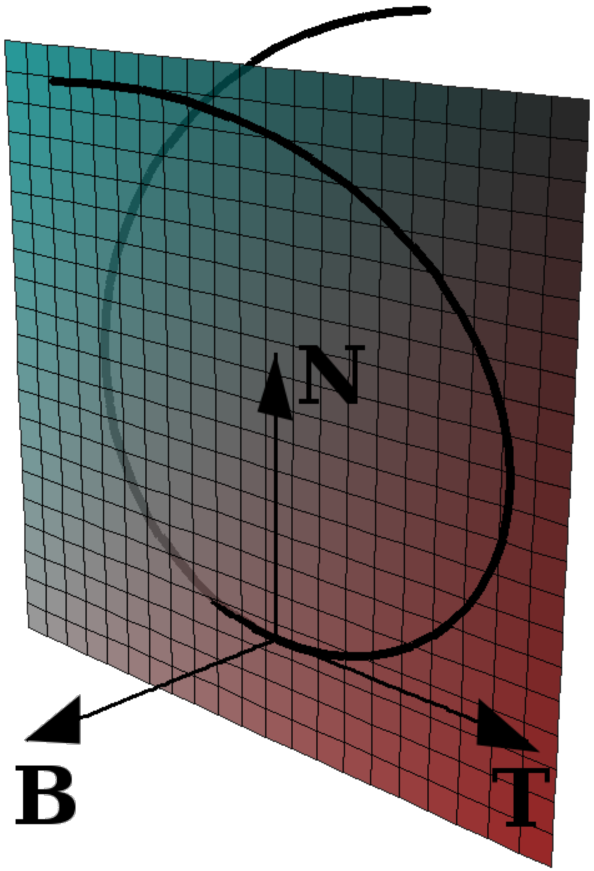
$$N_j = b_j \times t_j$$

Discrete Frenet frame

Discrete frame introduced in:
The resultant electric moment of complex molecules
Eyring, Physical Review, 39(4):746—748, 1932.

Frenet Frame: Issue

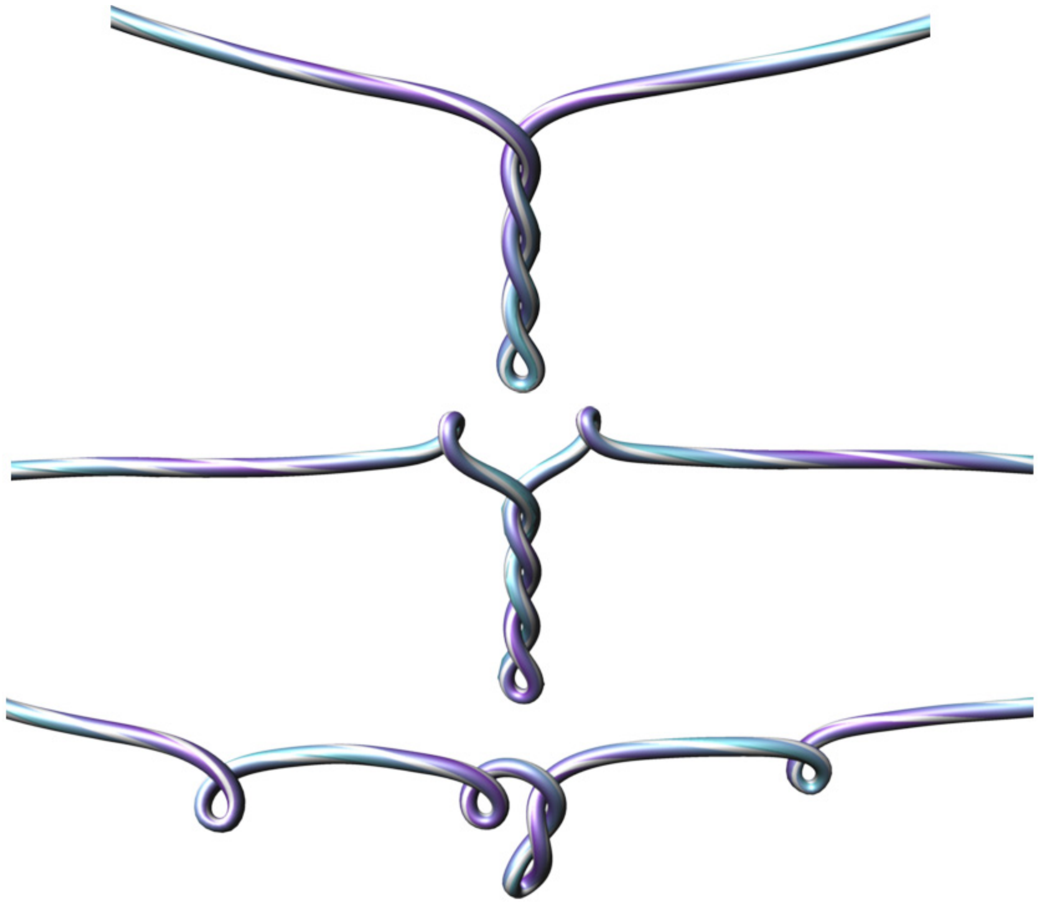
?



$$\frac{d}{ds}\begin{pmatrix} T \\ N \\ B \end{pmatrix} = \begin{pmatrix} 0 & \boxed{\kappa} & 0 \\ -\kappa & 0 & \tau \\ 0 & -\tau & 0 \end{pmatrix}\begin{pmatrix} T \\ N \\ B \end{pmatrix}$$

http://upload.wikimedia.org/wikipedia/commons/6/6f/Frenet.png

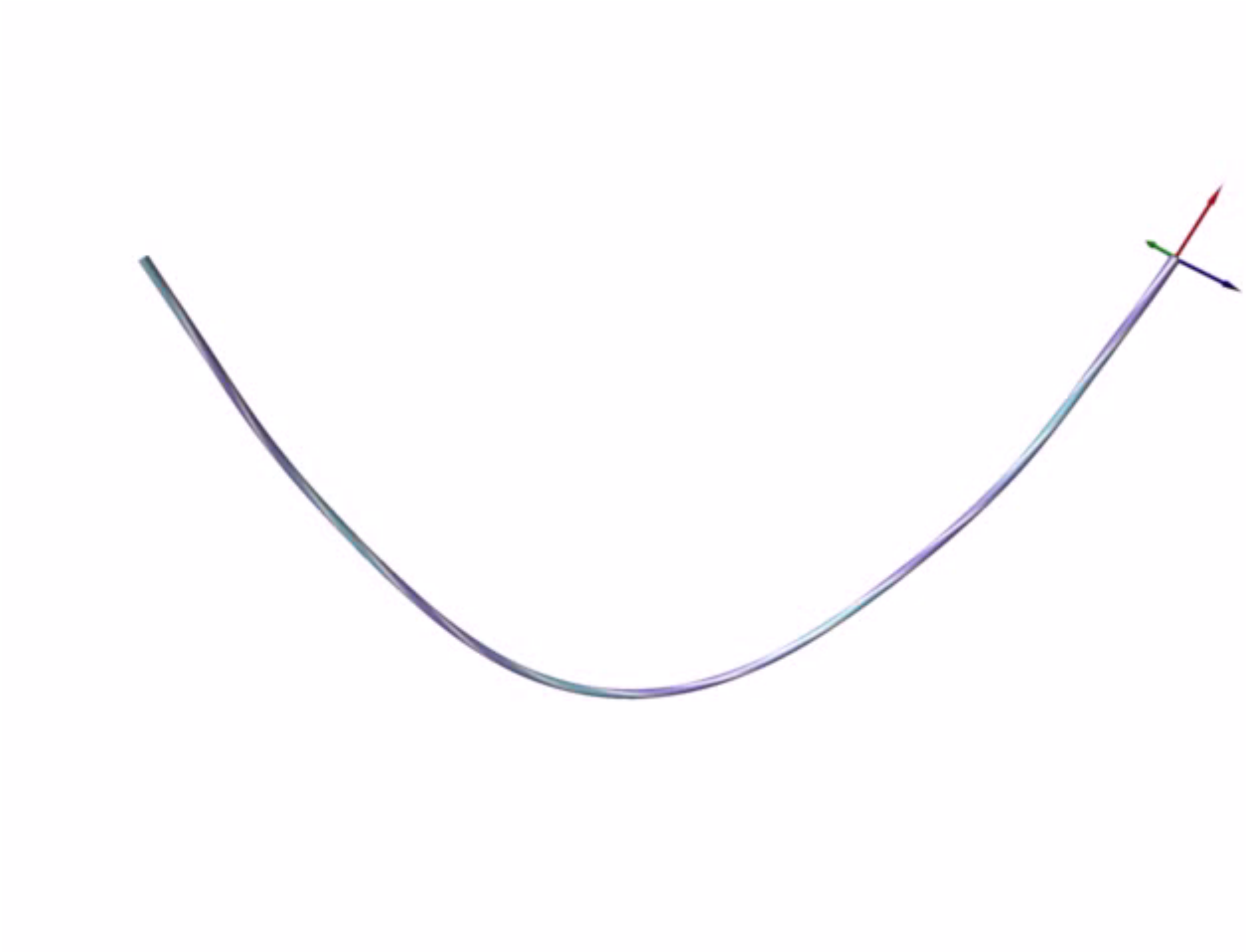
Segments Not Always Enough



Discrete Elastic Rods
Bergou, Wardetzky, Robinson, Audoly, and Grinspun
SIGGRAPH 2008

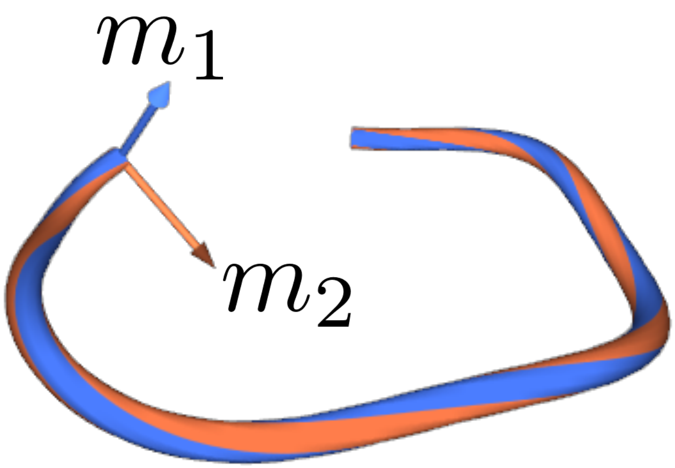
http://www.cs.columbia.edu/cg/rods/

Simulation Goal



http://www.cs.columbia.edu/cg/rods/

Adapted Framed Curve



$$\Gamma = \{\gamma(s); T, m_1, m_2\}$$

Material frame

http://www.cs.columbia.edu/cg/rods/

Normal part encodes twist

Bending Energy

$$E_{\text{bend}}(\Gamma) := \frac{1}{2}\int_{\Gamma} \alpha\kappa^2\, ds$$

Punish turning the steering wheel

$$\begin{aligned}
\kappa N &= T' \\
&= (T' \cdot T)T + (T' \cdot m_1)m_1 + (T' \cdot m_2)m_2 \\
&= (T' \cdot m_1)m_1 + (T' \cdot m_2)m_2 \\
&:= \omega_1 m_1 + \omega_2 m_2
\end{aligned}$$

Bending Energy

$$E_{\text{bend}}(\Gamma) := \frac{1}{2}\int_\Gamma \alpha(\omega_1^2 + \omega_2^2)\, ds$$

Punish turning the steering wheel

$$\begin{aligned}\kappa N &= T' \\ &= (T' \cdot T)T + (T' \cdot m_1)m_1 + (T' \cdot m_2)m_2 \\ &= (T' \cdot m_1)m_1 + (T' \cdot m_2)m_2 \\ &:= \omega_1 m_1 + \omega_2 m_2\end{aligned}$$

Twisting Energy

$$E_{\text{twist}}(\Gamma) := \frac{1}{2}\int_{\Gamma} \beta m^2 \, ds$$

Punish non-tangent change in material frame

$$\begin{aligned} m &:= m_1' \cdot m_2 \\ &= \frac{d}{dt}(m_1 \cdot m_2) - m_1 \cdot m_2' \\ &= -m_1 \cdot m_2' \end{aligned}$$

Twisting Energy

$$E_{\text{twist}}(\Gamma) := \frac{1}{2}\int_\Gamma \beta m^2\, ds$$

Punish non-tangent change in material frame

$$\begin{aligned} m &:= m_1' \cdot m_2 \\ &= \frac{d}{dt}(m_1 \cdot m_2) - m_1 \cdot m_2' \\ &= -m_1 \cdot m_2' \end{aligned}$$

Swapping and does not affect !

Which Basis to Use

THERE IS MORE THAN ONE WAY TO FRAME A CURVE

RICHARD L. BISHOP

The Frenet frame of a 3-times continuously differentiable (that is, C^3) non-degenerate curve in euclidean space has long been the standard vehicle for analysing properties of the curve invariant under euclidean motions. For arbitrary moving frames, that is, orthonormal basis fields, we can express the derivatives of the frame with respect to the curve parameter in terms of the frame itself, and due to orthonormality the coefficient matrix is always skew-symmetric. Thus it generally has three nonzero entries. The Frenet frame gains part of its special significance from the fact that one of the three derivatives is always zero. Another feature of the Frenet frame is that it is *adapted* to the curve: the members are either tangent to or perpendicular to the curve. It is the purpose of this paper to show that there are other frames which have these same advantages and to compare them with the Frenet frame.

1. Relatively parallel fields. We say that a normal vector field M along a curve is *relatively parallel* if its derivative is tangential. Such a field turns only whatever amount is necessary for it to remain normal, so it is as close to being parallel as possible without losing normality. Since its derivative is perpendicular to it, a relatively parallel normal field has constant length. Such fields occur classically in

Curve-Angle Representation

$$m_1 = u\cos\theta + v\sin\theta$$

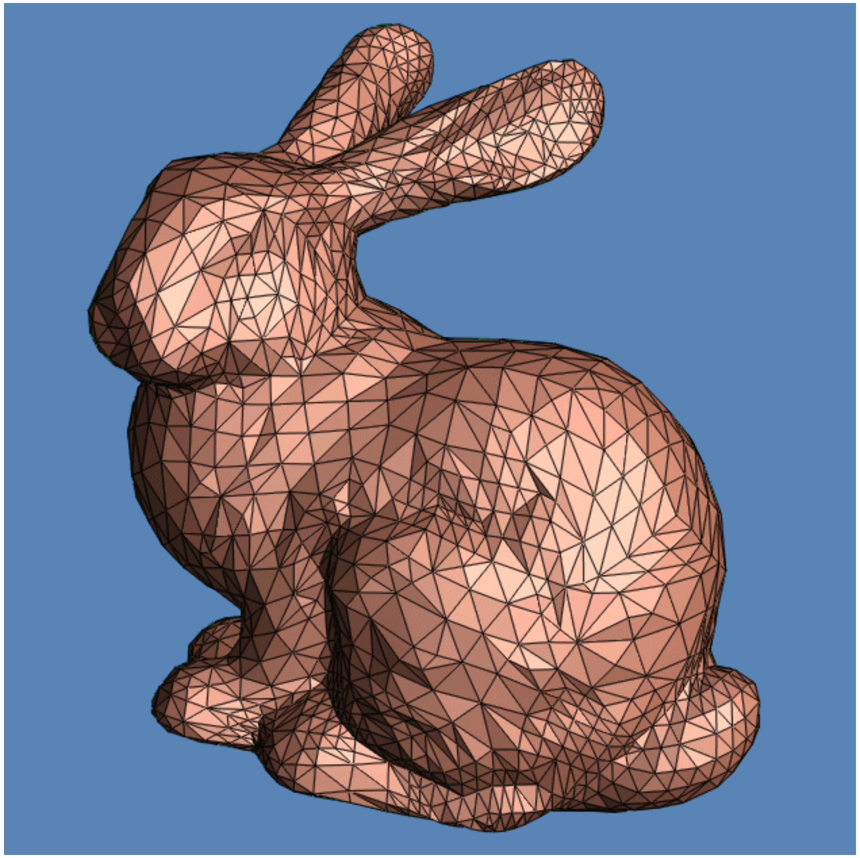
$$m_2 = -u\sin\theta + v\cos\theta$$

$$E_{\text{twist}}(\Gamma) := \frac{1}{2}\int_\Gamma \beta(\theta')^2\, ds$$

Degrees of freedom for elastic energy:

- Shape of curve
- Twist angle

Next



http://graphics.stanford.edu/data/3Dscanrep/stanford-bunny-cebal-ssh.jpg
http://www.stat.washington.edu/wxs/images/BUNMID.gif

Surfaces