1

CS-184: Computer Graphics

Lecture #13: Natural Splines, B-Splines, and NURBS

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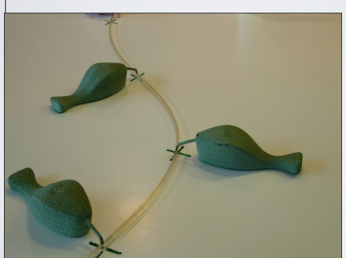
2

Natural Splines

- Draw a "smooth" line through several points



A real draftsman's spline.

Image from Carl de Boor's webpage.

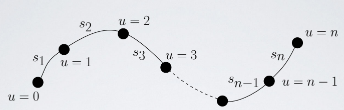
3

Natural Cubic Splines

- Given $n+1$ points
  - Generate a curve with n segments
  - Curves passes through points
  - Curve is C^2 continuous
- Use cubics because lower order is better...

4

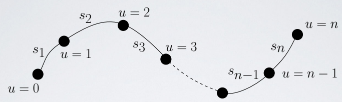
Natural Cubic Splines



$$\mathbf{x}(u) = \begin{cases} \mathbf{s}_1(u) & \text{if } 0 \le u < 1 \\ \mathbf{s}_2(u-1) & \text{if } 1 \le u < 2 \\ \mathbf{s}_3(u-2) & \text{if } 2 \le u < 3 \\ & \vdots \\ \mathbf{s}_n(u-(n-1)) & \text{if } n-1 \le u \le n \end{cases}$$

5

Natural Cubic Splines



$s_i(0) = p_{i-1}$	$i = 1 \dots n$	← n constraints
$s_i(1) = p_i$	$i = 1 \dots n$	← n constraints
$s_i'(1) = s_{i+1}'(0)$	$i = 1 \dots n-1$	← n-1 constraints
$s_i''(1) = s_{i+1}''(0)$	$i = 1 \dots n-1$	← n-1 constraints
$s_1''(0) = s_n''(1) = 0$		←2 constraints

Total 4n constraints

6

Natural Cubic Splines

- Interpolate data points
- No convex hull property
- Non-local support
  - Consider matrix structure...
- C^2 using cubic polynomials

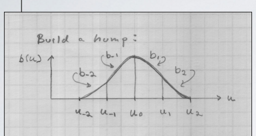
7

B-Splines

- Goal: C^2 cubic curves with local support
  - Give up interpolation
  - Get convex hull property
- Build basis by designing "hump" functions

8

B-Splines



$$\mathbf{b}(u) = \begin{cases} \mathbf{b_{-2}}(u) & \text{if } u_{-2} \leq u < u_{-1} \\ \mathbf{b_{-1}}(u) & \text{if } u_{-1} \leq u < u_{0} \\ \mathbf{b_{+1}}(u) & \text{if } u_{0} \leq u < u_{+1} \\ \mathbf{b_{+2}}(u) & \text{if } u_{+1} \leq u \leq u_{+2} \end{cases}$$

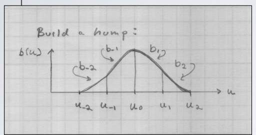
$b''_{-2}(u_{-2}) = b'_{-2}(u_{-2}) = b_{-2}(u_{-2}) = 0$ $\leftarrow 3$ constraints
$b''_{+2}(u_{+2}) = b'_{+2}(u_{+2}) = b_{+2}(u_{+2}) = 0$ $\leftarrow 3$ constraints

$b_{-2}(u_{-1}) = b_{-1}(u_{-1})$
$b_{-1}(u_0) = b_{+1}(u_0)$
$b_{+1}(u_{+1}) = b_{+2}(u_{+1})$
$\leftarrow$ [Repeat for b' and b''
3×3=9 constraints

Total 15 constraints ...... need one more

9

B-Splines



$$\mathbf{b}(u) = \begin{cases} \mathbf{b_{-2}}(u) & \text{if } u_{-2} \leq u < u_{-1} \\ \mathbf{b_{-1}}(u) & \text{if } u_{-1} \leq u < u_0 \\ \mathbf{b_{+1}}(u) & \text{if } u_0 \leq u < u_{+1} \\ \mathbf{b_{+2}}(u) & \text{if } u_{+1} \leq u \leq u_{+2} \end{cases}$$

$b''_{-2}(u_{-2}) = b'_{-2}(u_{-2}) = b_{-2}(u_{-2}) = 0$ ←3 constraints

$b''_{+2}(u_{+2}) = b'_{+2}(u_{+2}) = b_{+2}(u_{+2}) = 0$ ←3 constraints

$b_{-2}(u_{-1}) = b_{-1}(u_{-1})$

$b_{-1}(u_0) = b_{+1}(u_0)$

$b_{+1}(u_{+1}) = b_{+2}(u_{+1})$

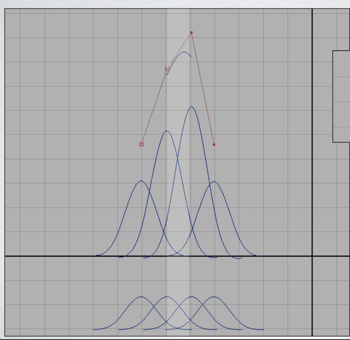
← Repeat for b' and b''; 3×3=9 constraints

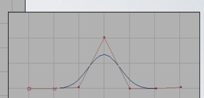
$b_{-2}(u_{-2}) + b_{-1}(u_{-1}) + b_{+1}(u_0) + b_{+2}(u_{+1}) = 1$ ←1 constraint (convex hull)

Total 16 constraints

10

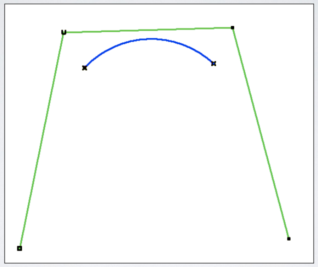
B-Splines





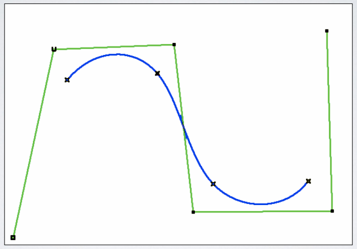
11

B-Splines



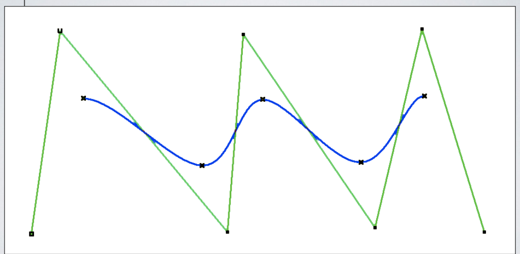
12

B-Splines



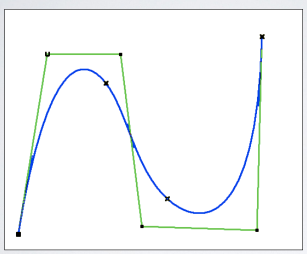
13

B-Splines



14

B-Splines



Example with end knots repeated

15

B-Splines

- Build a curve w/ overlapping bumps
- Continuity
  - Inside bumps C^2
  - Bumps "fade out" with C^2 continuity
- Boundaries
  - Circular
  - Repeat end points
  - Extra end points

16

B-Splines

- Notation
  - The basis functions are the $b_i(u)$
  - "Hump" functions are the concatenated function
    - Sometimes the humps are called basis... can be confusing
  - The u_i are the knot locations
  - The weights on the hump/basis functions are control points

17

B-Splines

- Similar construction method can give higher continuity with higher degree polynomials
- Repeating knots drops continuity
  - Limit as knots approach each other
- Still cubics, so conversion to other cubic basis is just a matrix multiplication

18

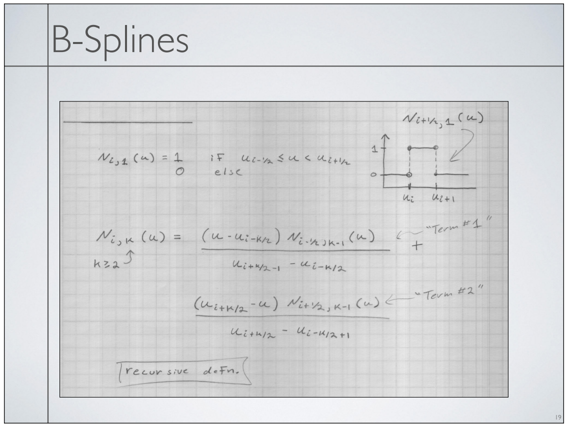
B-Splines

- Geometric construction
  - Due to Cox and de Boor
  - My own notation, beware if you compare w/ text
- Let hump centered on u_i be $N_{i,4}(u)$

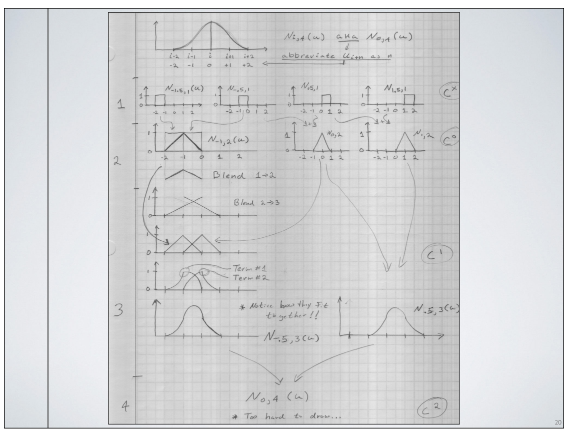
Cubic is order 4

$N_{i,k}(u)$ Is order k hump, centered at u_i

Note: i is integer if k is even
else $(i+1/2)$ is integer



19



20

21

NURBS

- **N**on**u**niform **R**ational **B**-**S**plines
  - Basically B-Splines using homogeneous coordinates
  - Transform under perspective projection
  - A bit of extra control

22

NURBS

$$\mathbf{p}_i = \begin{bmatrix} p_{ix} \\ p_{iy} \\ p_{iz} \\ p_{iw} \end{bmatrix}$$

$$\mathbf{x}(u) = \frac{\sum_i \begin{bmatrix} p_{ix} \\ p_{iy} \\ p_{iz} \end{bmatrix} N_i(u)}{\sum_i p_{iw} N_i(u)}$$

- Non-linear in the control points
- The p_{iw} are sometimes called "weights"