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DEPARTMENT OF COMPUTER GRAPHICS AND INTERACTION

CONVEX HULL IN 3 DIMENSIONS

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https://cw.felk.cvut.cz/doku.php/courses/a4m39vg/start

Based on [Berg], [Preparata], [Rourke] and [Boissonnat]

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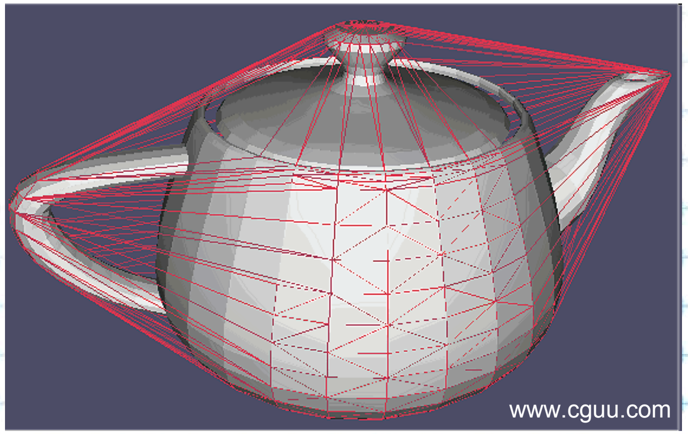
Talk overview

- Lower bounds for convex hull in 2D and 3D
- Other criteria for CH algorithm classification
- Recapitulation of CH algorithms
- Terminology refresh
- Convex hull in 3D
  - Terminology
  - Algorithms
    - Gift wrapping
    - D&C Merge
    - Randomized Incremental



Lower bounds for Convex hull

- O(*n* log *n*) in E^2, E^3
- O(*n h*), where h is number of CH facets
  – output sensitive algs.
- O(*n*) for sorted points and for polygon
- O(log *n*) for new point insertion in online algs.

Other criteria for CH algorithm classification

- Optimality – depends on data order (or distribution)

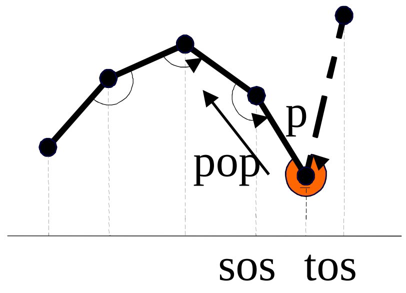
  In worst case x In expected case

- Output sensitivity – depends on the result
- Extendable to higher dimensions?
- Off-line versus on-line
  - Off-line – all points available, preprocessing for search speedup
  - On-line – stream of points, new point p_i on demand, just one new point at a time, CH valid for $\{p_1, p_2, \ldots, p_r\}$
  - Real-time – points come as they "want"

    (not faster than optimal constant O(log n) inter-arrival delay)
- Parallelizable
- Dynamic – points can be deleted

Why to search other convex hull algorithms?

- Graham scan
  O(n log n) time and O(n) space is

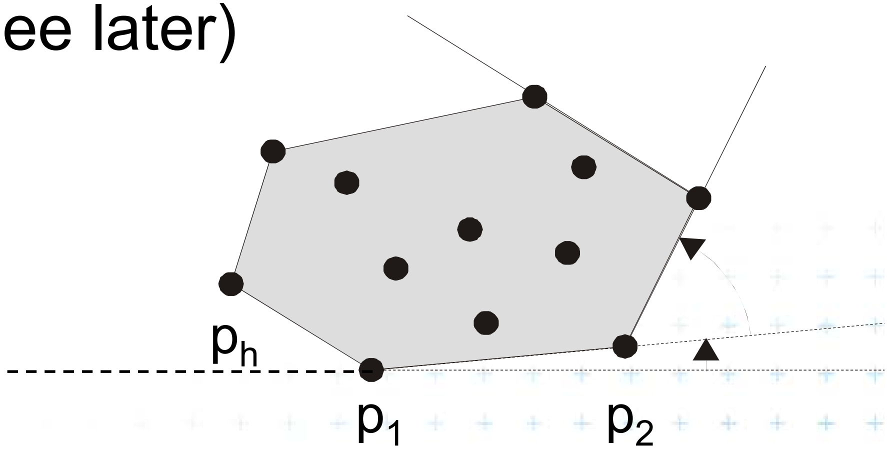


  – optimal in worst case
  – not optimal in average case (not output sensitive)
  – only 2D
  – off-line
  – serial (not parallel)
  – not dynamic

$O(n)$ for polygon (will be discussed in seminar [9])

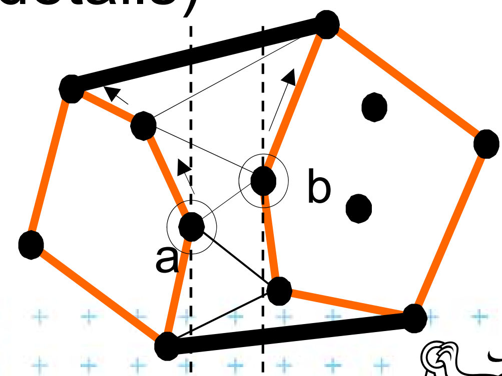
Jarvis March – Gift wrapping

- *O*(*hn*) time and O(*n*) space is
  - not optimal in worst case $O(n^2)$
  - may be optimal if *h* << *n* (output sensitive)
  - 3D or higher dimensions (see later)
  - off-line
  - serial (not parallel)
  - not dynamic



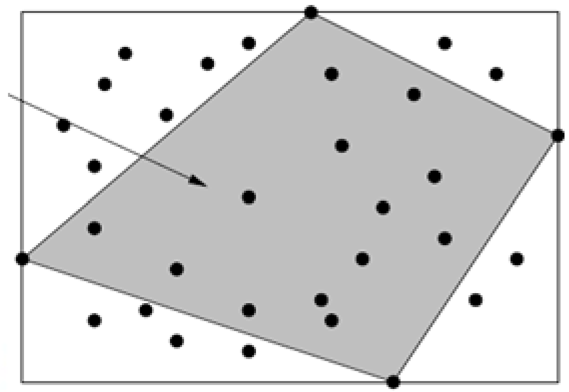
Divide & Conquer

- O(*n* log *n*) time and O(*n*) space is
  - optimal in worst case (in 2D or 3D)
  - not optimal in average case (not output sensitive)
  - 2D or 3D (circular ordering), in higher dims not optimal
  - off-line
  - Version with sorting (the presented one) – serial
  - Parallel for overlapping merged hulls
    (see Chapter 3.3.5 in Preparata for details)
  - not dynamic



Quick hull

- O(n log n) expected time, O(n^2) the worst case and O(n) space *in 2D* is
  - not optimal in worst case O(n^2)
  - optimal if uniform distribution then $h \ll n$ (output sensitive)
  - 2D, or higher dimensions [see http://www.qhull.org/]
  - off-line
  - serial (not parallel)
  - not dynamic



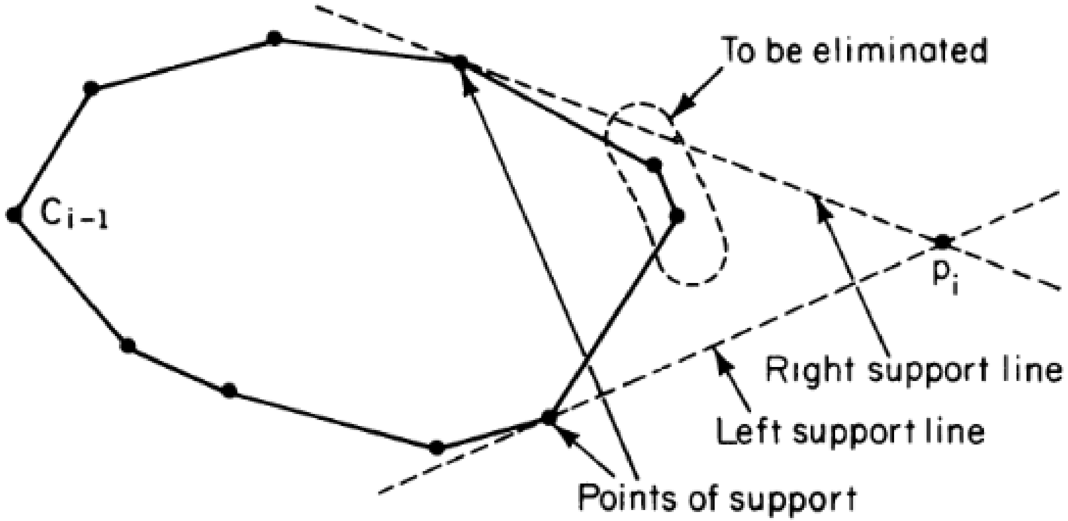
[Mount]

Chan

- *O*(*n* log *h*) time and O(*n*) space is
  - optimal for *h* points on convex hull (output sensitive)
  - 2D and 3D --- gift wrapping
  - off-line
  - Serial (not parallel)
  - not dynamic

Preparata's on-line algorithm

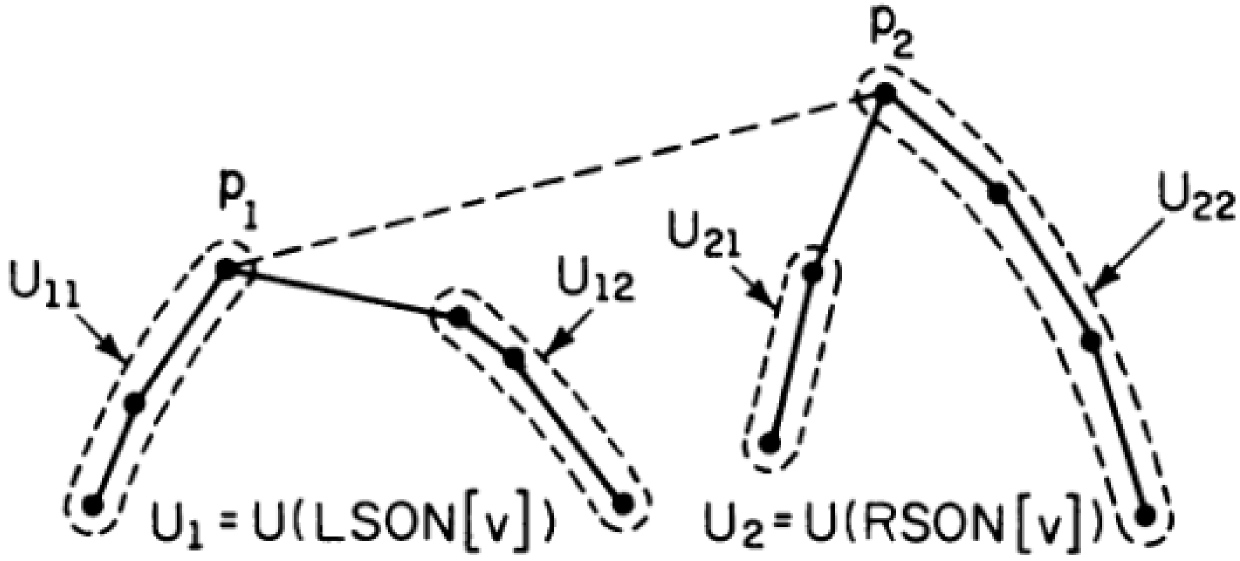
- New point *p* is tested
  - Inside –> ignored
  - Outside –> added to hull
    - Find left and right supporting lines (touch at supporting points)
    - Remove points between supporting points
    - Add *p* to CH between supporting lines



[Preparata]

Overmars and van Leeuven

- Allow dynamic CH
  (on-line insert & delete)
- Manage special tree with all intermediate CHs
- Will be discussed on seminar [7]



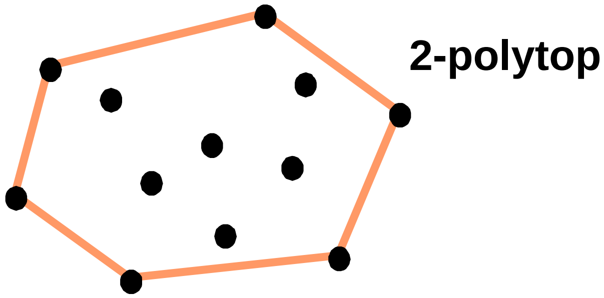
[Preparata]

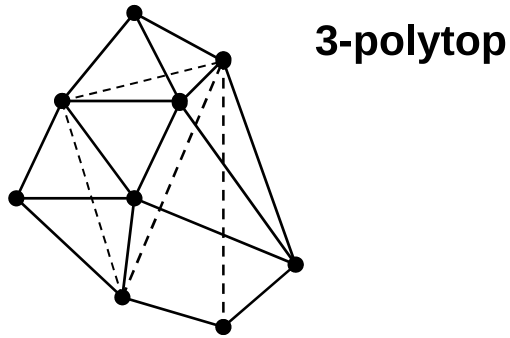
Convex hull in 3D

- Terminology
- Algorithms
  1. Gift wrapping
  2. D&C Merge
  3. Randomized Incremental

Terminology

- Polytope (d-polytope)
  = convex hull of finite set of points in E^d





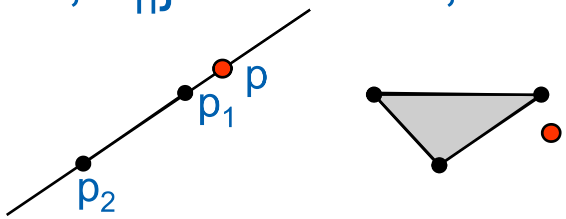
- Simplex (k-simplex, d-simplex)
  = CH of $k + 1$ affine independent points

  = "Special" Polytope with all the points are on the CH

Terminology (2)

- **Affine combination**
  = linear combination of the points $\{p_1, p_2, \ldots, p_n\}$
  whose coefficients $\{\lambda_1, \lambda_2, \ldots, \lambda_n\}$ sum to 1, and $\lambda_i \in R$

$$\sum_{i=1}^{n} \lambda_i p_i$$



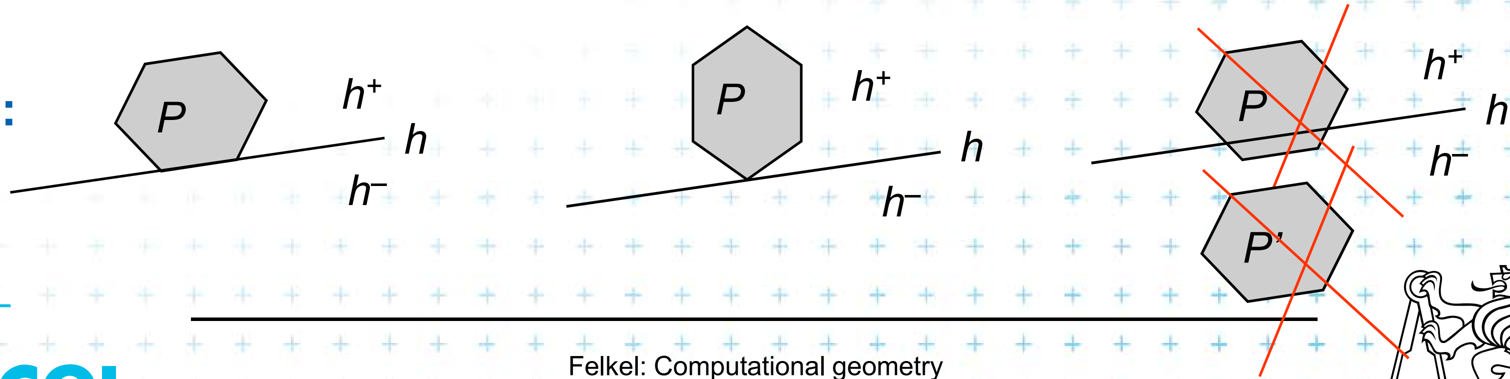
- **Affine independent points**
  = no one point can be expressed as affine combination of the others

- **Convex combination**
  = linear combination of the points $\{p_1, p_2, \ldots, p_n\}$
  whose coefficients $\{\lambda_1, \lambda_2, \ldots, \lambda_n\}$ sum to 1, and $\lambda_i \in R^+_0$
  (i.e., $\forall i \in \{1,\ldots,k\}, \lambda_i \geq 0$)

Terminology (3)

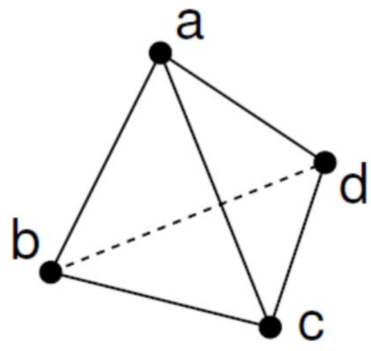
- Any (d-1)-dimensional hyperplane *h* divides the space into (open) halfspaces h^+ *and* h^-, *so that* $E^n = h^+ \cup h \cup h^-$
- *Def:* $\overline{h^+} = h^+ \cup h$, $\overline{h^-} = h^- \cup h$ (closed halfspaces)
- Hyperplane supports a polytope *P* (Supporting hyperplane)
  - if $h \cap P$ is not empty and
  - if *P* is entirely contained within either $\overline{h^+}$ or $\overline{h^-}$

In 2D:



Faces and facets

- Face of the polytope
  = Intersection of polytope *P* with a supporting hyperplane *h*
  - Faces are convex polytops of dimension *d* ranging from 0 to d – 1
  - 0-face = vertex
  - 1-face = edge
  - (d – 1)-face = facet



Proper faces:
Vertices: a,b,c,d
Edges: ab, ac, ad, bc, bd, cd
Facets: abc, abd, bcd

In 3D we often say *face*, but it means correctly a *facet*

Proper faces

- Proper faces

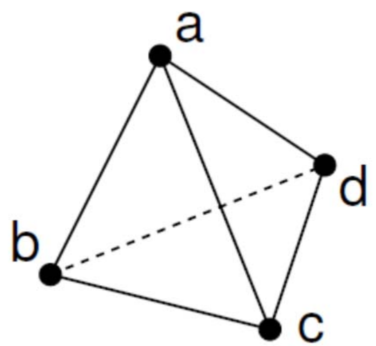
  = Faces of dimension *d* ranging from 0 to *d* – 1

- Improper faces

  = proper faces + two additional faces:

  – {} = Empty set = face of dimension -1

  – Entire polytope = face of dimension *d*



Improper faces:

Empty set {}

Vertices: a,b,c,d

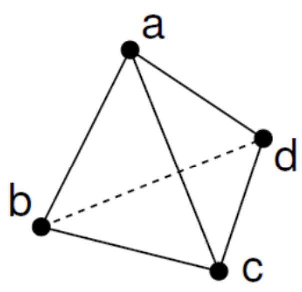
Edges: ab, ac, ad, bc, bd, cd

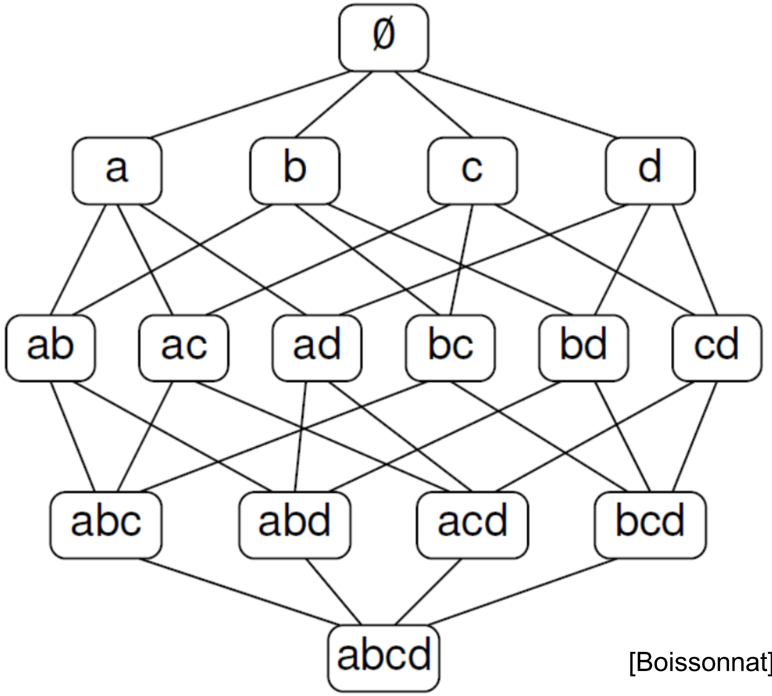
Facets: abc, abd, bcd

Entire polytope: abcd

Incident graph

- Stores topology of the polytope
- Ex: 3-simplex:





[Boissonnat]

Dimension

-1

0

1

2

3

- D-simplex is very regular face structure:
  - 1-face for each pair of vertices
  - 2-face for each triple of vertices

Facts about polytopes

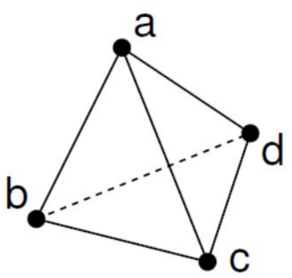
- Boundary o polytope is *union of its proper faces*
- Polytope has *finite number of faces (next slide)*. Each face is a polytope
- Polytope is *convex hull of its vertices (the def)* (its bounded)
- Polytope is the *intersection of finite number of closed halfspaces* $\overline{h^+}$
  (conversely not: intersection of closed halfspaces may be unbounded => called polyhedron or unbounded polytope)

Number of faces on a d-simplex

- Number of *j*-dimensional faces on a *d*-simplex = number of (*j*+1)-element subsets from domain of size (*d*+1)

$$\binom{d+1}{j+1} = \frac{(d+1)!}{(j+1)!(d-j)!}$$

- Ex.: Tetrahedron = 3-simplex:



  – facets (2-dim. faces) $\binom{3+1}{2+1} = \frac{4!}{3!1!} = 4$

  – edges (1-dim. faces) $\binom{3+1}{1+1} = \frac{4!}{2!2!} = 6$

  – vertices (0-dim faces) $\binom{3+1}{0+1} = \frac{4!}{1!3!} = 4$

Complexity of 3D convex hull is O(n)

- The worst case complexity → if all *n* points on CH

=> use 3-simplex for complexity derivation

1. has all points on its surface – on the Convex Hull
2. has usually more edges E and faces F than 3-polytope
3. has triangular facets, each generates 3 edges, shared by 2 triangles => 3F = 2E   2-manifold

- V – E + F = 2   … Euler formula for V = n points

V – E + 2E/3 = 2

V – 2 = E / 3

E = 3V – 6,   V = n

E = O(n)

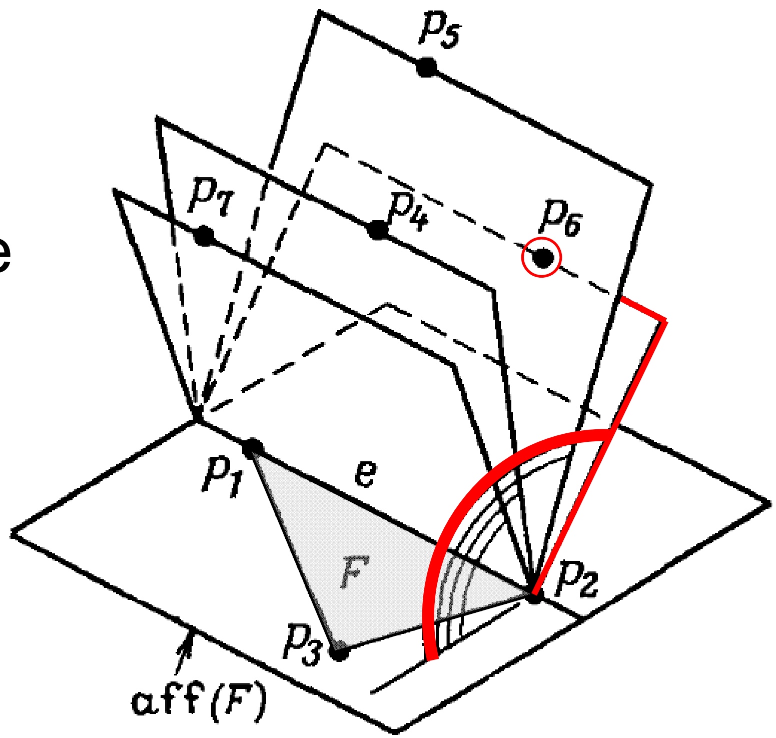
F = 2E / 3

F = 2V – 4

F = O(n)

1. Gift wrapping in higher dimensions

- First known algorithm for n-dimensions (1970)
- Direct extension of 2D alg.
- Complexity O(nF)
  - F is number of CH facets
  - Algorithm is output sensitive
  - Details on seminar, assignment [10]



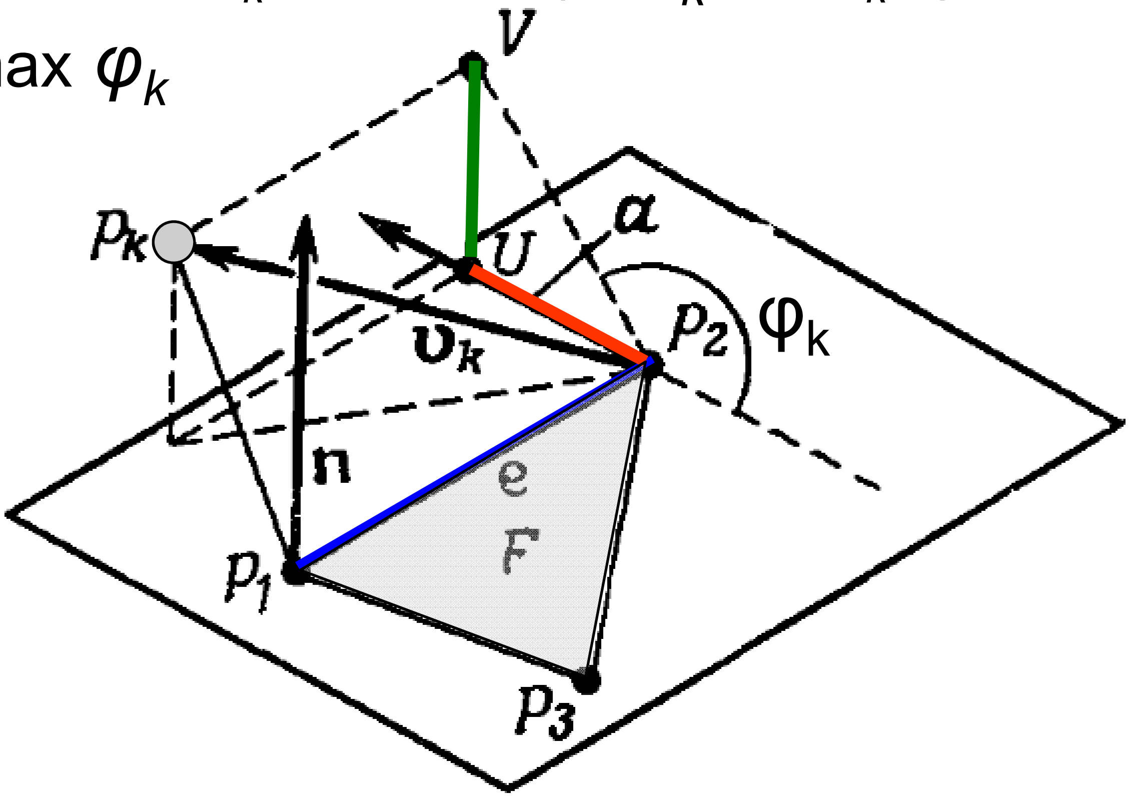
[Preparata]

The angle comparison [Preparata 3.4.1]

Cotangent of the agle φ_k between halfplanes *F* and ep_k
$= -\ |UP_2|\ /\ |UV|$, where $|UP_2| = \boldsymbol{v}_k.\boldsymbol{a}$ and $|UV| = \boldsymbol{v}_k.\boldsymbol{n}$

For each P_k compute $\varphi_k = \text{arcctan}(-\ \boldsymbol{v}_k.\boldsymbol{a}\ /\ \boldsymbol{v}_k.\boldsymbol{n})$,

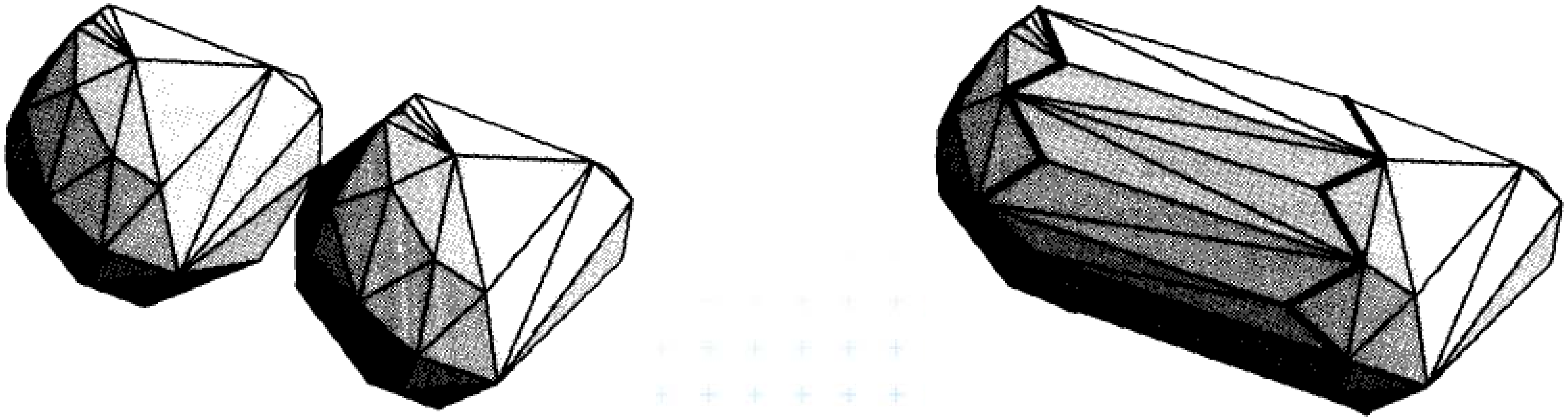
The angle is max φ_k



[Preparata]

2. Divide & conquer 3D convex hull [Preparata, Hong77]

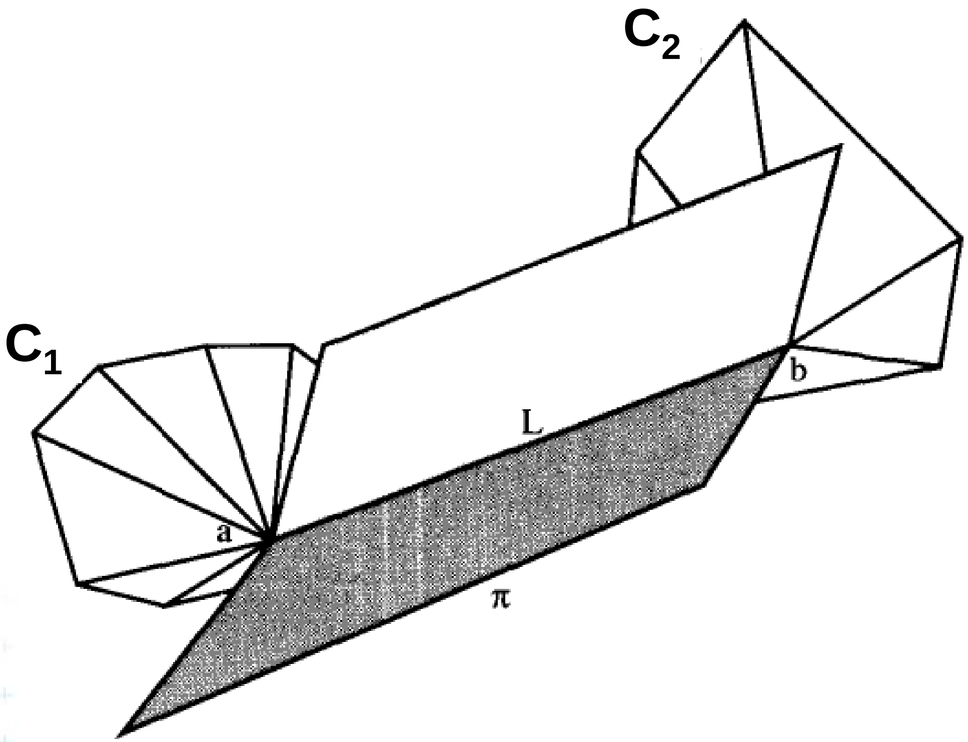
- Sort points in x-coord
- Recursively split, construct CH, merge
- Merge takes O(n) => O(*n* log *n*) total time



[Rourke]

Divide & conquer 3D convex hull [Preparata, Hong 77]

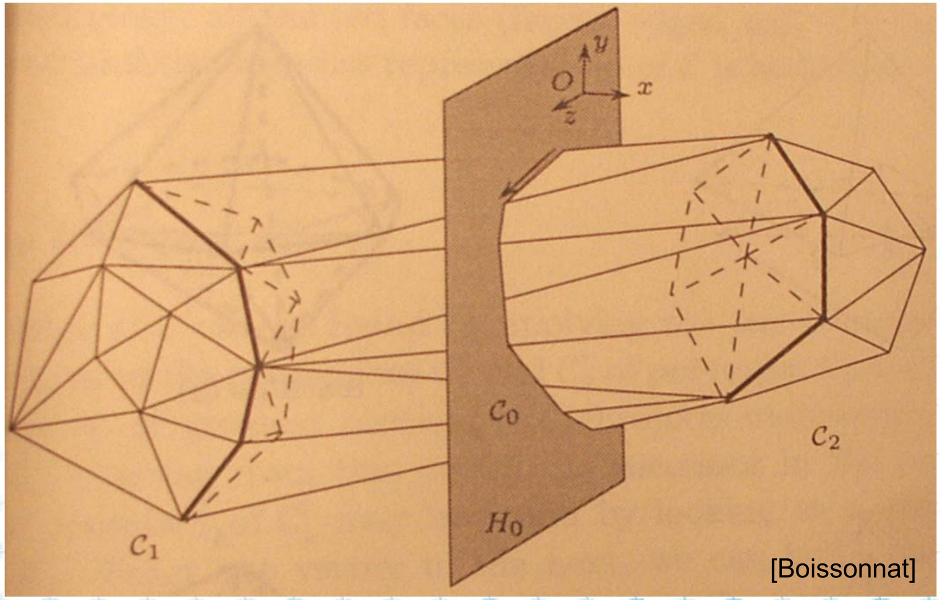
- Merge(C_1 with C_2) uses gift wrapping
  - Gift wrap plane around edge *e* – find new point *p* on C_1 or on C_2 (neighbor of *a* or *b*)
  - Search just the CW or CCW neighbors around *a, b*



[Rourke]

Divide & conquer 3D convex hull [Preparata, Hong 77]

- Performance O(*n* log *n*) rely on circular ordering
  - In 2D: Ordering of points around CH
  - In 3D: Ordering of vertices around 2-polytop C_0 (vertices on intersection of new CH edges with separating plane H_0) [ordering around horizon of C_1 and C_2 does not exist, both horizons may be non-convex and even not simple polygons]



[Boissonnat]

  - In ≥ 4D: Such ordering does not exist

Divide & conquer 3D convex hull [Preparata, Hong 77]

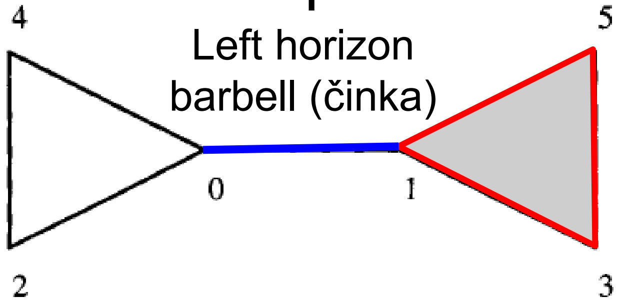
Merge(C_1 with C_2)

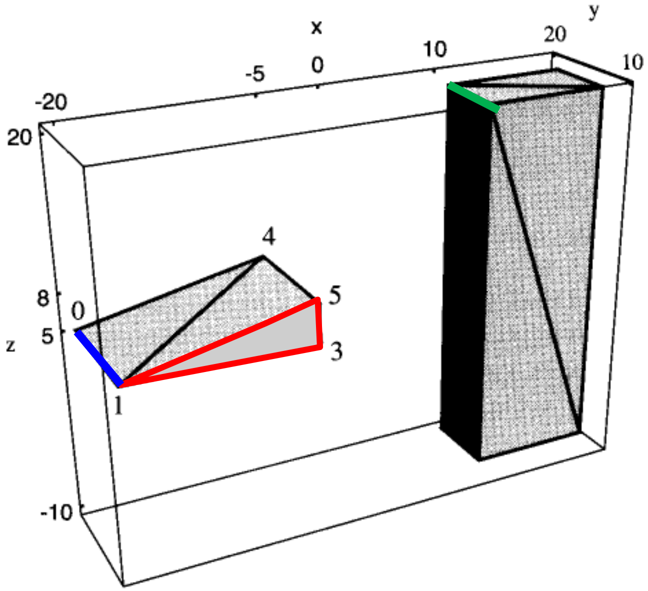
- Find the first CH edge *L* connecting C_1 with C_2
- *e* = *L*
- While not back at *L do*
  - store *e* to *C*
  - Gift wrap plane around edge *e* – find new point *P* on C_1 or on C_2 (neighbor of *a* or *b*)
  - *e* = new edge to just found end-point *P*
  - Store new triangle *eP* to *C*
- Discard hidden faces inside CH from *C*
- Report merged convex hull *C*

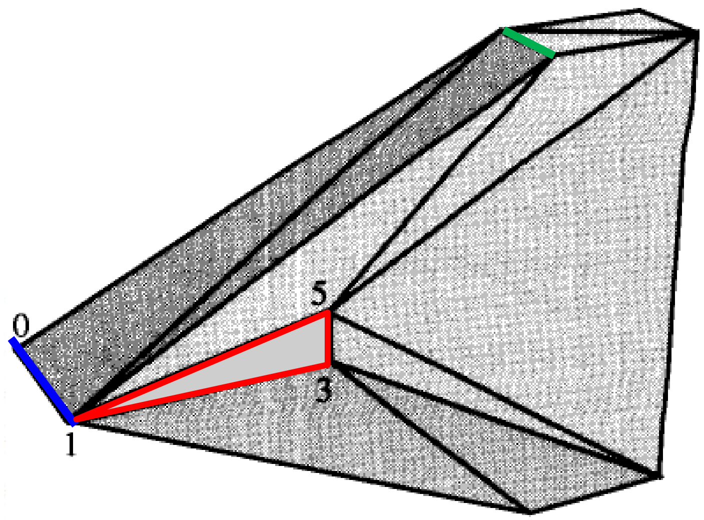
Divide & conquer 3D convex hull [Preparata, Hong 77]

- Problem of gift wrapping [Edelsbrunner 88]
  - The edges on horizon do not form simple circle but a "barbell" 0,2,4,0,1,3,5,1

Do not stop here!







[Berg]

3. Randomized incremental alg. principle

1. Create tetrahedron (smallest CH in 3D)
   - Take 2 points p_1 and p_2
   - Search the 3[rd] point not lying on line p_1p_2
   - Search the 4[th] point not lying in plane $p_1p_2p_3$ …if not found, use 2D CH
2. Perform random permutation of remaining points $\{p_5, \dots, p_n\}$
3. For p_r in $\{p_5, \dots, p_n\}$ do add point p_r to CH(P_{r-1})

   Notation: for $r \geq 1$ let $P_r = \{p_1, \dots, p_r\}$ is set of already processed pts

   - If p_r lies inside or on the boundary of CH(P_{r-1}) then do nothing
   - If p_r lies outside of CH(P_{r-1}) then
     - find and remove visible faces
     - create new faces (triangles) connecting p_r with lines of horizon

[Berg]

Conflict graph

- Stores unprocessed points with facets of CH they see
- Bipartite graph

  points p_t, $t > r$ … unprocessed points

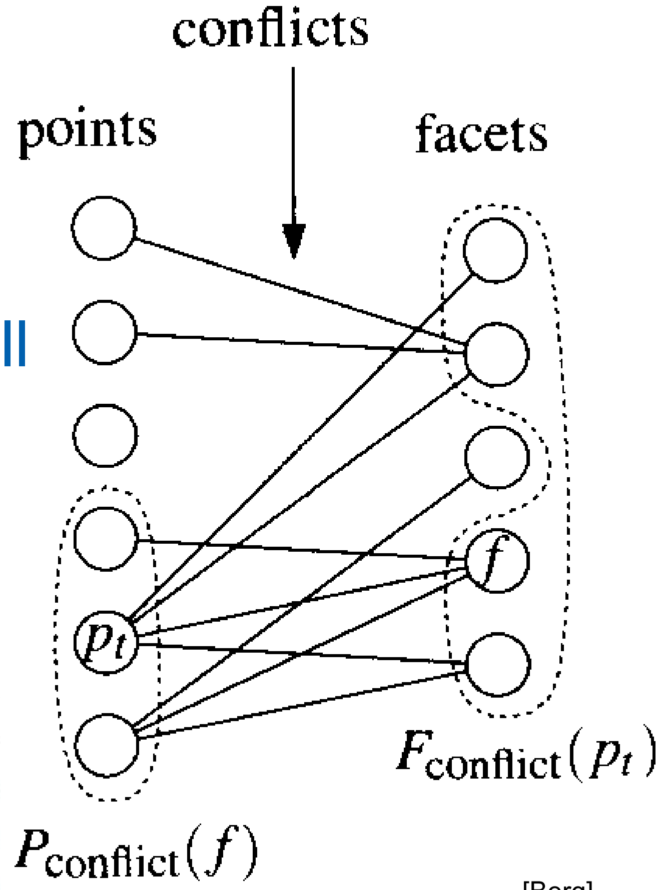
  facets of CH(P_r)… facets of convex hull

  conflict arcs … conflict, as visible facets cannot be in CH

- Maintains sets:

  $P_{conflict}(f)$ … points, that see f

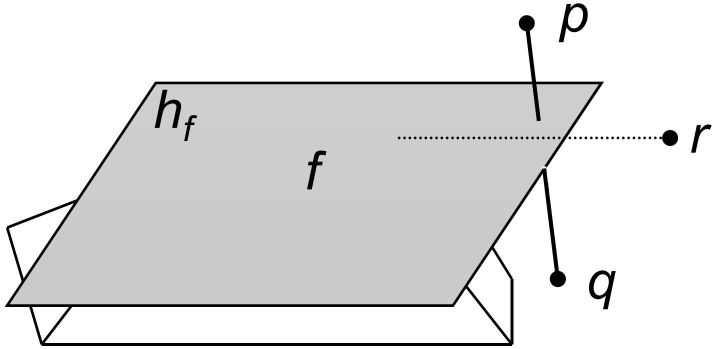
  $F_{conflict}(p_r)$… facets visible from p_r (visible region – deleted after insertion of p_r)



[Berg]

Visibility between point and face

- Face f is visible from a point p if that point lies in the open half-space on the other side of h_f than the polytope



f is visible from p (p is *above* the plane)

f is not visible from r lying *in the plane* of f (this case will be discussed next)

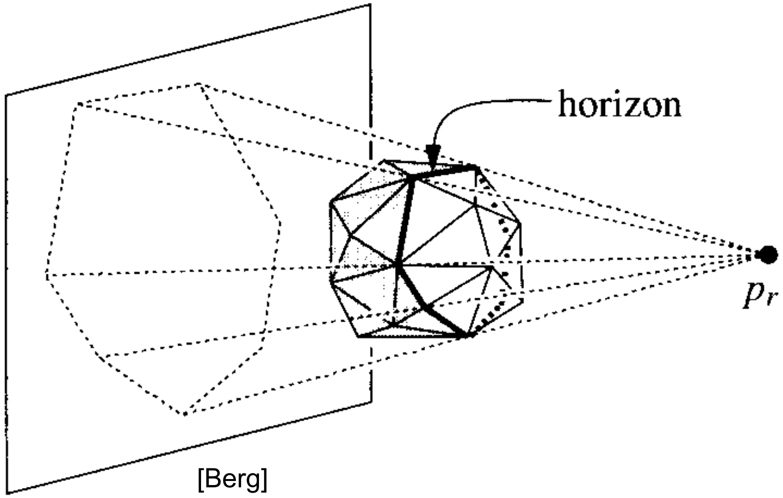
f is not visible from q

$p \in P_{conflict}(f)$, p is among the points that see the face f

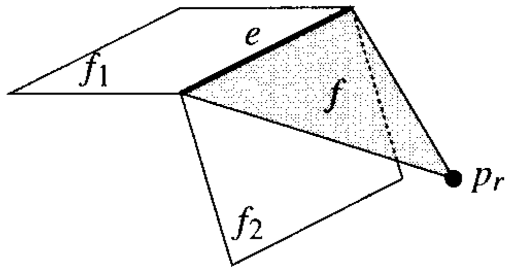
$f \in F_{conflict}(p)$ f is among the faces that visible from point p

New triangles to horizon

- Horizon = edges *e* incident to visible and invisible facets



[Berg]



[Berg]

- New triangle *f* connects edge *e* on horizon and point p_r and
  - creates new node for facet f updates the conflict graph
  - add arcs to points visible f (subset from $P_{coflict}(f_1) \cup P_{coflict}(f_2)$)
- Coplanar triangles on the plane ep_r are merged with new triangle. Conflicts are copied from the deleted triangle (same plane)

Incremental Convex hull algorithm

IncrementalConvexHull(P)

Input: Set of n points in general position in 3D space

Output: The convex hull C=CH(P) of P

1. Find four points that form an initial tetrahedron, C = CH($\{p_1, p_2, p_3, p_4\}$)
2. Compute random permutation $\{p_5, p_6, \ldots, p_n\}$ of the remaining points
3. Initialize the conflict graph with all visible pairs (p_t, f), where f is facet of C and p_t, $t > 4$, are non-processed points
4. **for** r = 5 to n **do** …insert p_r, into C
5. **if**($F_{conflict}(p_r)$ is not empty) **then** …p_r is outside, any facet is visible
6. Delete all facets $F_{conflict}(p_r)$ from C … only from hull C, not from G
7. Walk around visible region boundary, create list L of horizon edges
8. **for** all $e \in L$ **do**
9. connect e to p_r by a new triangular facet f
10. **if** f is coplanar with its neighbor facet f' along e
11. **then** merge f and f', take conflict list from f'
12. **else** … determine conflicts for new face f

… [continue on the next slide]

Incremental Convex hull algorithm (cont…)

else … not coplanar => determine conflicts for new face *f*
Create node for *f* in *G* *//… new face in conflict graph G*
Let f_1 and f_2 be the facets incident to *e* in the old $CH(P_{r-1})$
$P(e) = P_{coflict}(f_1) \cup P_{coflict}(f_2)$
for all points $p \in P(e)$ **do**
if *f* is visible from *p*, **then** add(*p, f*) to *G* *… new edges*
Delete the node corresponding to p_r and the nodes corresponding to facets in $F_{coflict}(p_r)$ from *G*, together with their incident arcs
return C

Complexity: Convex hull of a set of points in E^3 can be computed in $O(n \log n)$ randomized expected time

For proof see: [Berg, Section11.3]

Conclusion

- Recapitulation of 2D algorithms
- 3D algorithms
  - Gift wrapping
  - D&C
  - Randomized incremental

References

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