

DCGI

KATEDRA POČÍTAČOVÉ GRAFIKY A INTERAKCE

Introduction to 3D geometry

Jiří Bittner

Outline

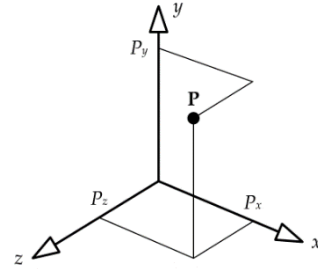
- Points, Vectors, Transformations MPG – chapter 21
- Camera and Projection MPG – chapter 9
- 3D Scene Representation MPG - chapters 5.11,
5.12, 5.13, 6-8, 14

Points in 3D

- Point is a location in 3D space

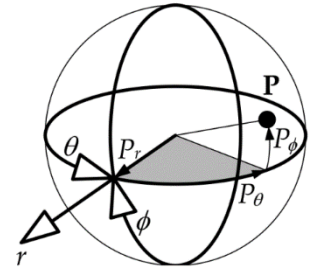
- Cartesian coordinates
 - Orthonormal basis

$$P = \begin{bmatrix} 2 \\ 3 \\ 1 \end{bmatrix}$$



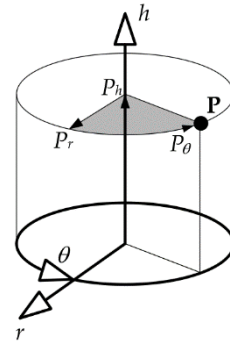
- Spherical coordinates

$$P = \begin{bmatrix} 90^\circ \\ 20^\circ \\ 1 \end{bmatrix}$$



- Cylindrical coordinates

$$P = \begin{bmatrix} 90^\circ \\ 3 \\ 1 \end{bmatrix}$$



Cartesian coordinates

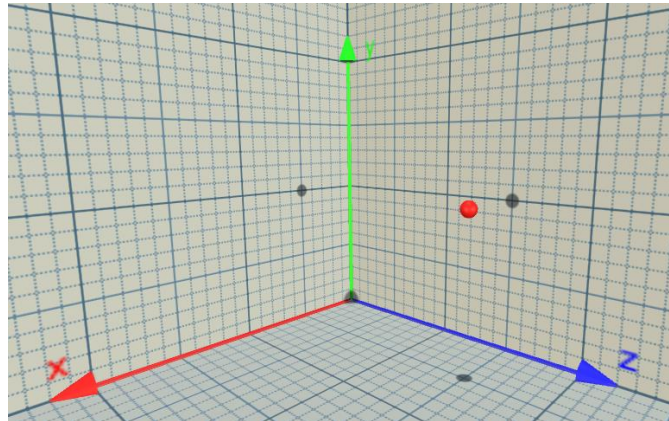
■ Axes

- Orthogonal directions
- Meet at origin
- Uniform scale
- Orthogonal basis

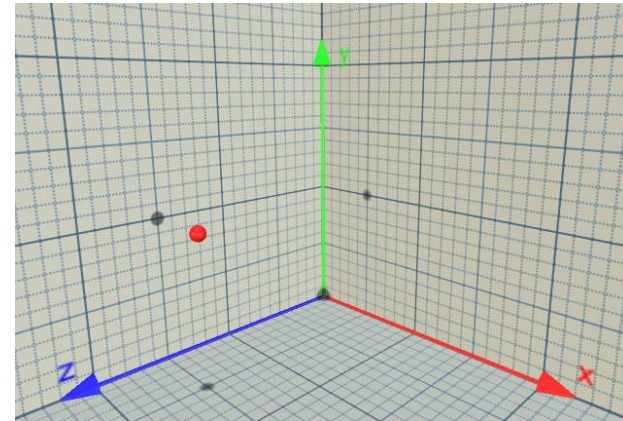
(René Descartes, 1596-1650)

$$A = [5, 10, 15]$$

$$A = \begin{bmatrix} 5 \\ 10 \\ 15 \end{bmatrix}$$



LHS
Direct3D, Unity, ...



RHS
OpenGL

Linear Transformations

- Scale (Uniform + Non-uniform)
- Mirror
- Shear
- Rotation

$$\begin{bmatrix} x' \\ y' \\ z' \end{bmatrix} = \begin{bmatrix} 3 \times 3 \\ \text{transformation} \\ \text{matrix} \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix}$$

Homogeneous coordinates

- Need also: translation, perspective projection
- Add 4-th coordinate

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} \rightarrow \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix} \approx \begin{bmatrix} x_h \\ y_h \\ z_h \\ w \end{bmatrix} \quad x = \frac{x_h}{w}, y = \frac{y_h}{w}, z = \frac{z_h}{w}$$

- For directions (points in infinity) $w = 0$

Transformation in homogeneous coordinates

- Finally normalize (divide by w)
 - Perspective division

$$\begin{bmatrix} x' \\ y' \\ z' \\ w' \end{bmatrix} = \begin{bmatrix} 4x4 \\ \text{transformation} \\ \text{matrix} \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ w \end{bmatrix}$$

$$\begin{bmatrix} x'' \\ y'' \\ z'' \end{bmatrix} = \begin{bmatrix} \frac{x'}{w'} \\ \frac{y'}{w'} \\ \frac{z'}{w'} \end{bmatrix}$$

Composing transformations

- Matrix multiplication

$$M = R \cdot T \cdot S \dots$$

- Associative

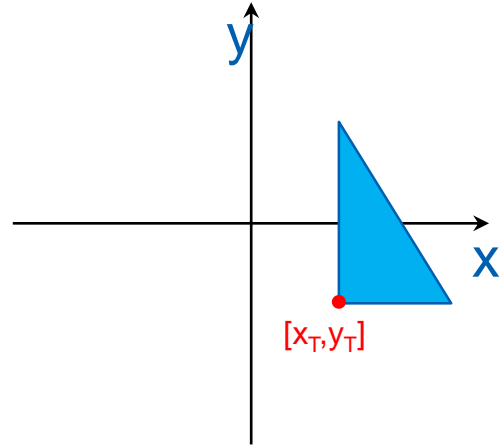
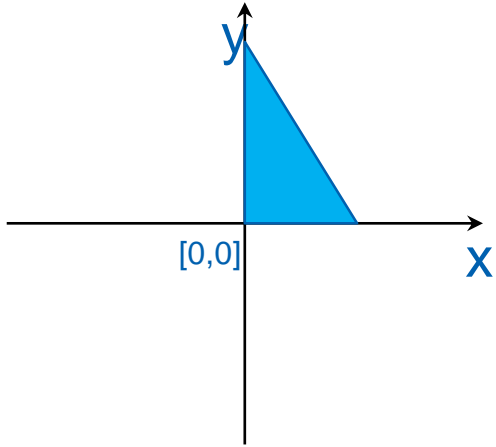
$$A \cdot (B \cdot C) = (A \cdot B) \cdot C$$

- Non-commutative: Transformation order matters!

$$A \cdot B \neq B \cdot A$$

- Transformations applied from right to left

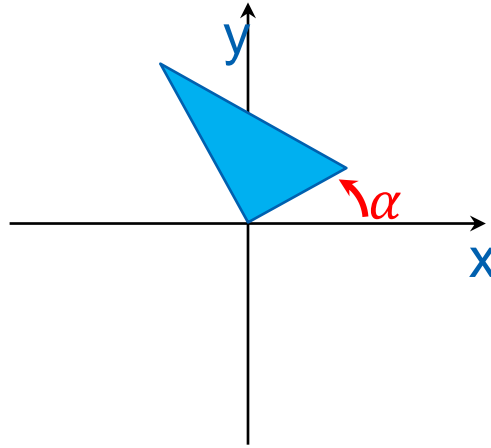
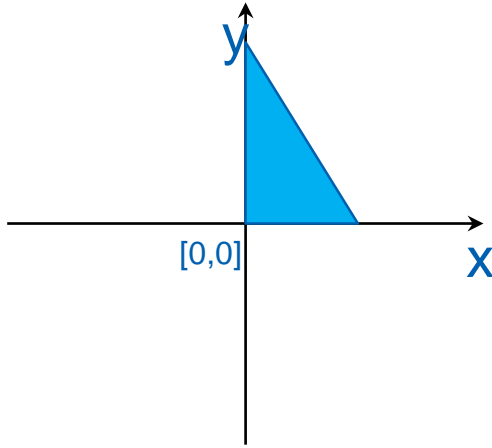
Translation



$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = M_T \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix},$$

$$M_T = \begin{bmatrix} 1 & 0 & 0 & t_x \\ 0 & 1 & 0 & t_y \\ 0 & 0 & 1 & t_z \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Rotation



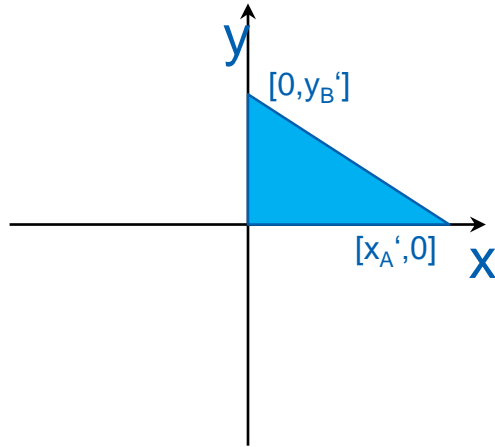
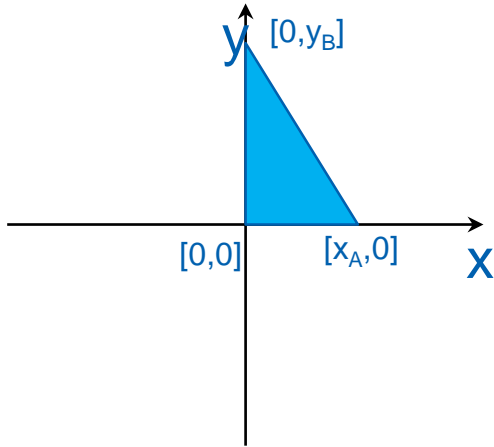
$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = M_{R_z} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix},$$

$$M_{R_z} = \begin{bmatrix} \cos \alpha & -\sin \alpha & 0 & 0 \\ \sin \alpha & \cos \alpha & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Euler angles

$$M = M_{R_x} M_{R_y} M_{R_z}$$

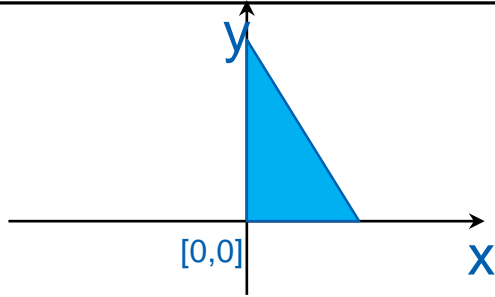
Scaling



$$\begin{bmatrix} x' \\ y' \\ z' \\ 1 \end{bmatrix} = M_S \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix},$$

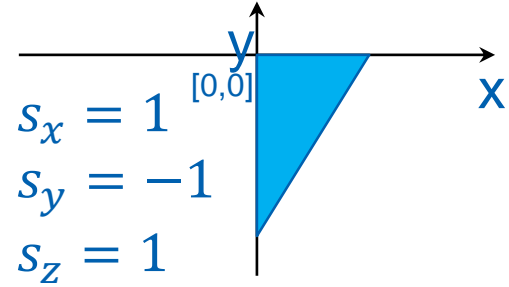
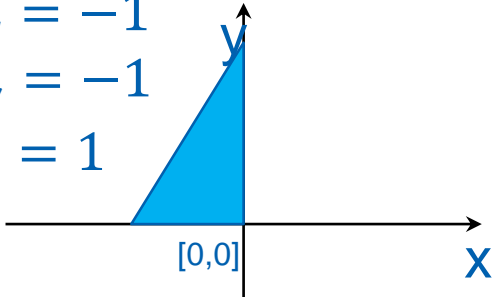
$$M_S = \begin{bmatrix} s_x & 0 & 0 & 0 \\ 0 & s_y & 0 & 0 \\ 0 & 0 & s_z & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Symetry



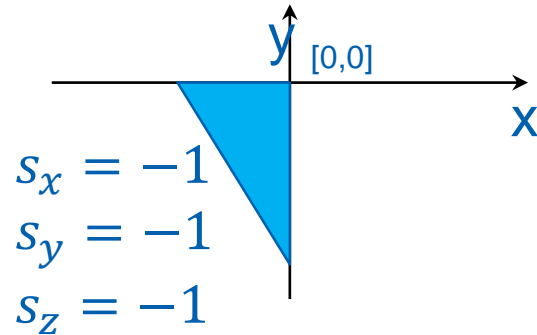
$$M_S = \begin{bmatrix} s_x & 0 & 0 & 0 \\ 0 & s_y & 0 & 0 \\ 0 & 0 & s_z & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$\begin{aligned} s_x &= -1 \\ s_y &= -1 \\ s_z &= 1 \end{aligned}$$



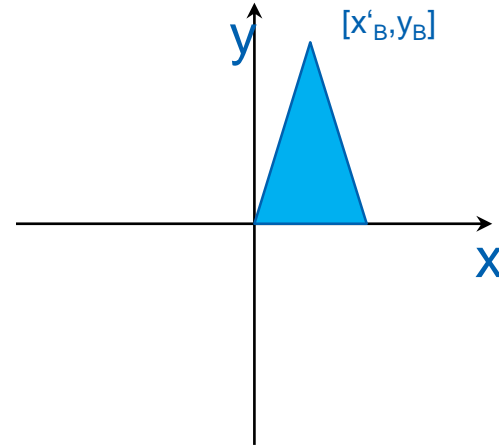
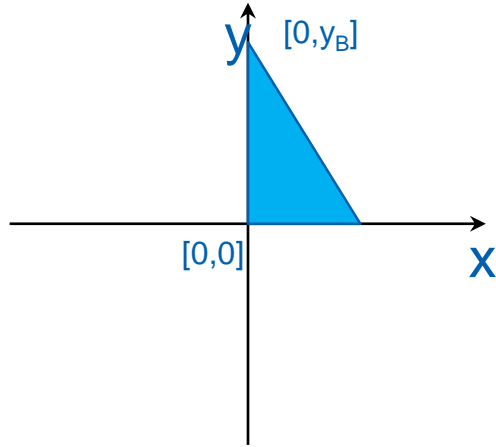
$$\begin{aligned} s_x &= 1 \\ s_y &= -1 \\ s_z &= 1 \end{aligned}$$

Try to avoid: Odd number of -1 flips polygon orientations!



$$\begin{aligned} s_x &= -1 \\ s_y &= -1 \\ s_z &= -1 \end{aligned}$$

Shear

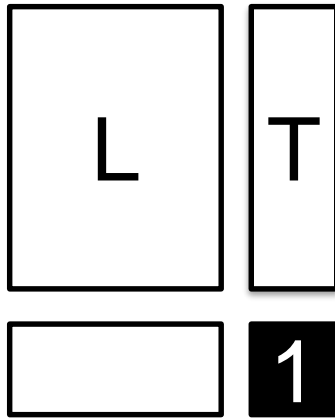


$$M_{SH_x} = \begin{bmatrix} 1 & SH_x & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

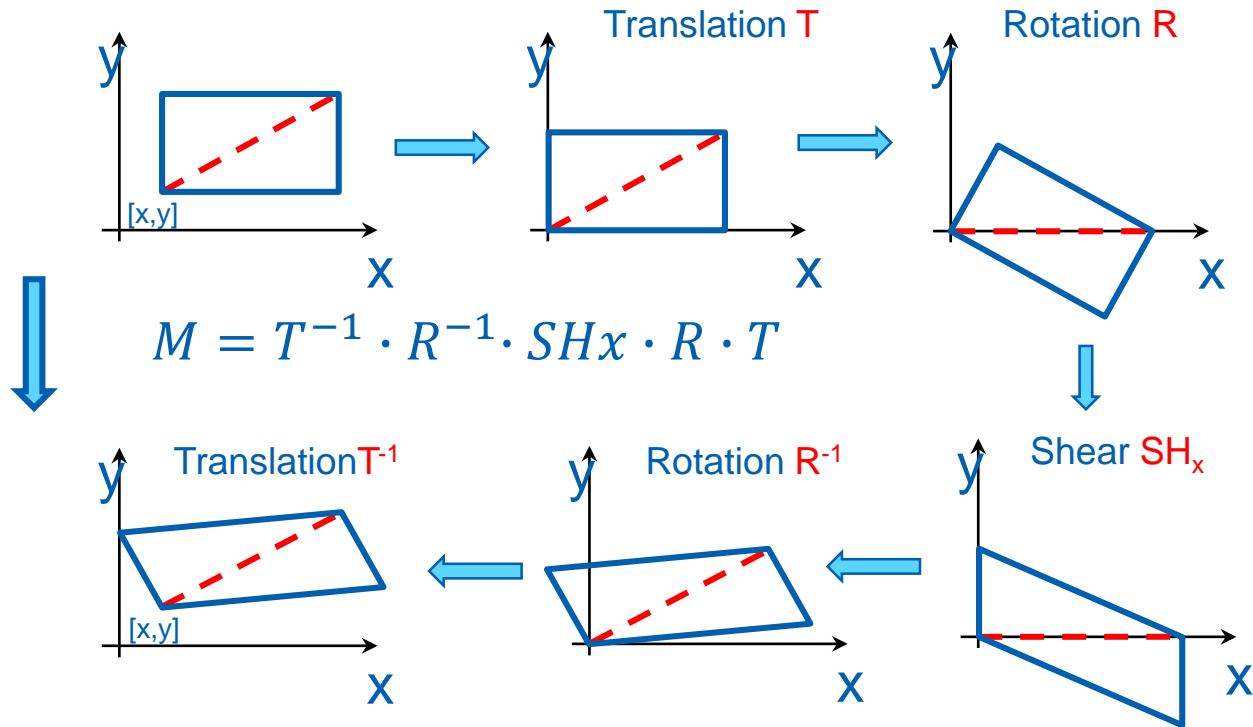
$$SH_x = \frac{x'_B}{y_B}$$

Transformation matrix

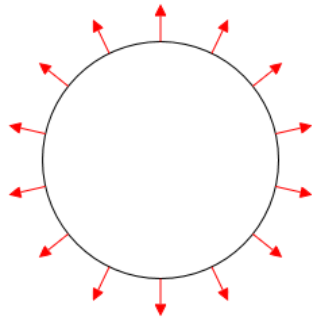
- L: linear transformation
- T: translation
- Last row (0, 0, 0, 1) for all affine transformations



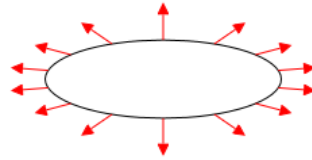
Example – shear along a diagonal



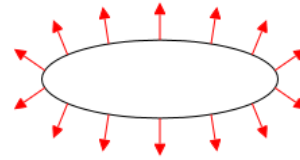
Transforming normals



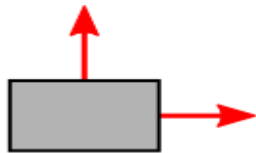
non-uniform scale



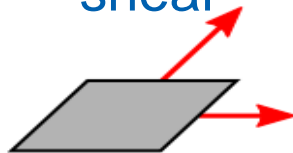
wrong



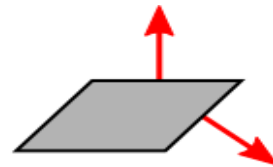
correct



shear

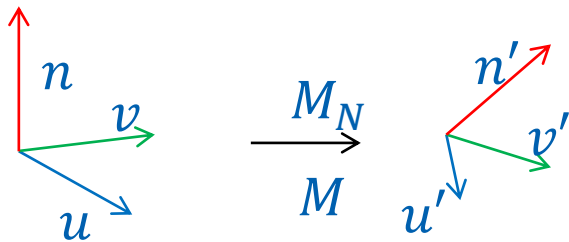


wrong



correct

Transforming normals



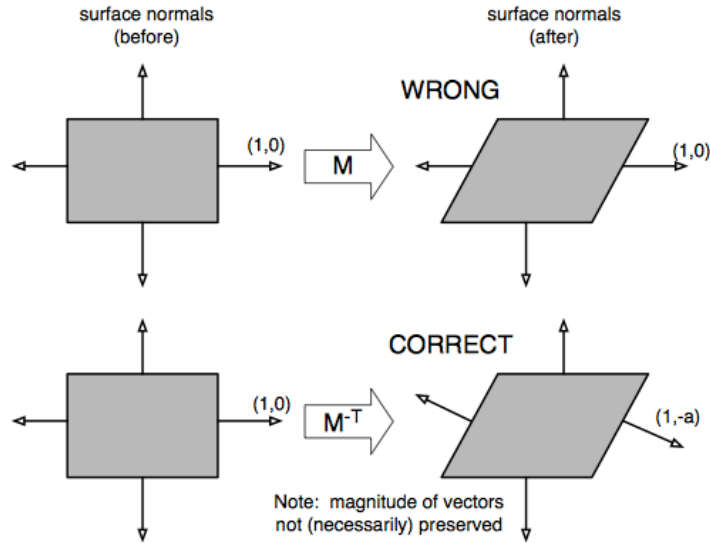
$$\begin{bmatrix} n_x' \\ n_y' \\ n_z' \\ 0 \end{bmatrix} = M_N \begin{bmatrix} n_x \\ n_y \\ n_z \\ 0 \end{bmatrix}$$

$$\begin{aligned} n^T u &= 0 \\ n'^T u' &= 0 \\ n'^T M u &= 0 \\ n'^T M u &= n^T u \\ n'^T M &= n^T \\ M^T n' &= n \\ n' &= M^{T^{-1}} n \\ n' &= M^{-1T} n \end{aligned}$$

Can use just 3x3 submatrix of M !

Transforming normals - example

$$M = \begin{bmatrix} 1 & a \\ 0 & 1 \end{bmatrix} \quad M^{-T} = \begin{bmatrix} 1 & 0 \\ -a & 1 \end{bmatrix}$$



Source: Stack Overflow

DEMO

<https://cent.felk.cvut.cz/predmety/39PHA/demos/transformations.html>

Transformation example



Model matrix

1	0	0	0
0	1	0	0
0	0	1	0
0	0	0	1

Reset

View matrix (read only)

1	0	0	0
0	1	0	0
0	0	1	0
0	0	0	1

Reset

Quaternions

- Alternative rotation representation
- Generalization of complex numbers
 - three basis elements i, j, k
 - $i^2 = j^2 = k^2 = i j k = -1, ij = -ji = k, jk = -kj = i, ki = -ik = j$
- Quaternion is a 4-tuple

$$\mathbf{q} = [x, y, z, w]$$

$$\mathbf{q} = i x + j y + k z + w = [\mathbf{v}, w]$$

$$\mathbf{v} = [x, y, z] = i x + j y + k z$$

$$\mathbf{q} = (x, y, z, w) = (\mathbf{v}, r) , \mathbf{v} = xi + yj + zk$$

Quaternions and Rotation

- Unit quaternion ($|q| = 1$) represents rotation in 3D

$$q = \left[a \sin \frac{\alpha}{2}, \cos \frac{\alpha}{2} \right]$$

3D rotation about axis a by angle α

Quaternion Operations

- Sum $q_1 + q_2 = [v_1 + v_2, w_1 + w_2]$

- Dot product $q_1 \cdot q_2 = v_1 \cdot v_2 + w_1 \cdot w_2$

- **Multiplication** (Hamilton product)

$$q_1 * q_2 = [v_1, r_1] * [v_2, r_2] = [r_1 v_2 + r_2 v_1 + v_1 \times v_2, r_1 r_2 - v_1 v_2]$$

- *Composition of rotations* (associative, non-commutative)

- **Conjugate**

$$q^* = [-v, r]$$

- Inverse rotation

Transformation with quaternion

- Express vector as quaternion

$$\mathbf{u} = (x, y, z, 0)$$

- Rotation of \mathbf{u} using q

$$\mathbf{u}' = (x', y', z', 0) = q * \mathbf{u} * q^*$$

- Two quaternion multiplications + conjugate

Quaternion to Rotation Matrix

- Quaternion $\mathbf{q} = [x, y, z, w]$ corresponds to rotation matrix

$$\mathbf{R} = \begin{pmatrix} 1 - 2y^2 - 2z^2 & 2xy - 2wz & 2xz + 2wy \\ 2xy + 2wz & 1 - 2x^2 - 2z^2 & 2yz - 2wx \\ 2xz - 2wy & 2yz + 2wx & 1 - 2x^2 - 2y^2 \end{pmatrix}$$

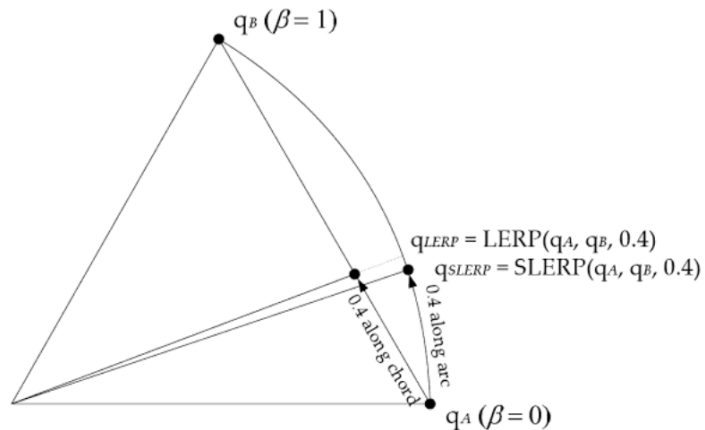
- Rotation composition faster with quaternions
- Vector transformation faster with matrix

Rotation Interpolation

- Matrix interpolation
 - breaks orthonormality - artefacts
- Quaternion interpolation
 - Linear interpolation (LERP)
 - Spherical linear interpolation (SLERP) - constant angular step

LERP and SLERP

$$q = \frac{w_A q_A + w_B q_B}{|w_A q_A + w_B q_B|}$$



J. Gregory, Game Engine Architecture

LERP

$$w_A = 1 - \beta$$

$$w_B = \beta$$

SLERP

$$w_A = \frac{\sin(1 - \beta)\theta}{\sin \theta}$$

$$w_B = \frac{\sin \beta \theta}{\sin \theta}$$

$$\theta = \text{acos } q_A q_B$$

Transformation Representation - SQT

- SQT (SRT)
 - Scale, Quaternion, Translation
- Uniform scale: $1+4+3 = 8$ scalars
 - Sequence of SQT can be composed to SQT
- Non-uniform scale: $3+4+3=10$ scalars
- Correct interpolation of rotation, scale and translation !
- Compact representation
- Fast composition of transformations
- Slower application of transformation

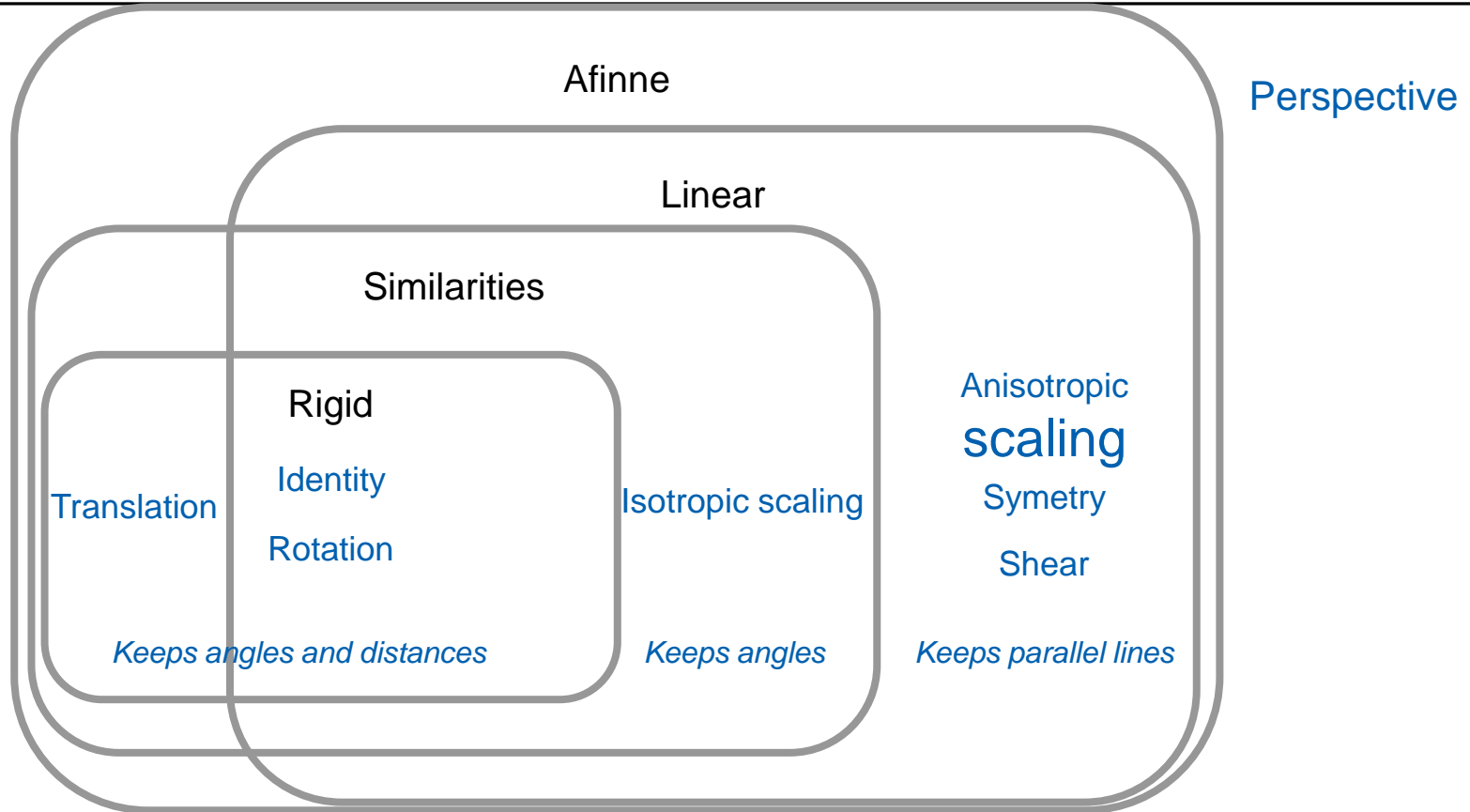
Transformation Representation - Matrix

- Matrix 4x4
- General affine transformation + perspective
- Simple concatenation (matrix multiplication)
- Fast application of transformation

Transformation – Summary

- Interpolation and composition of rotations – use quaternions (animations)
- Applying (many) transformations – use matrices (rendering)
- Conversions between representations

Transformations



Outline

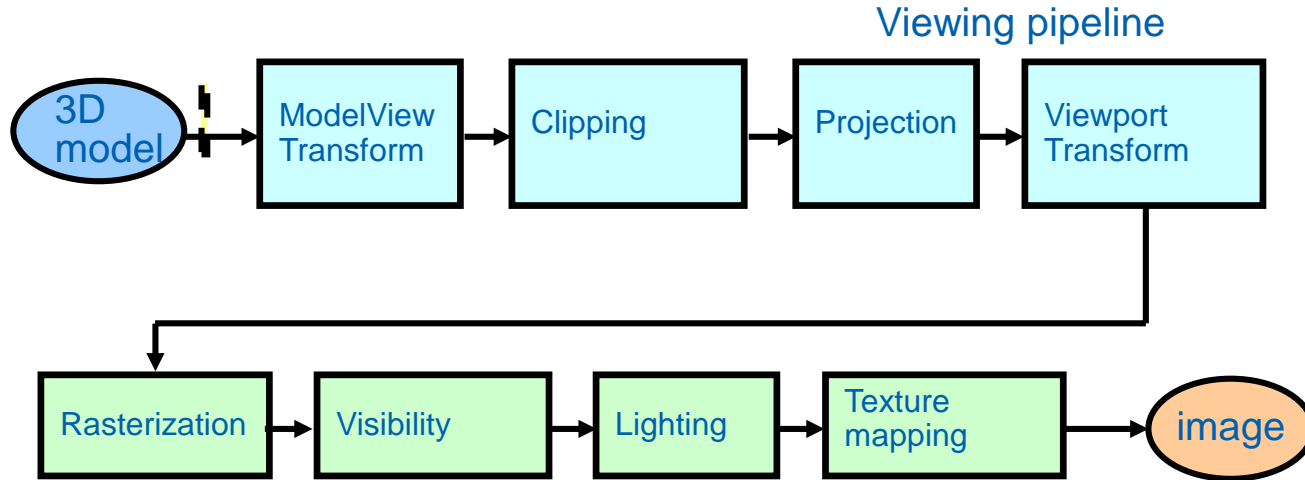
- Points, Vectors, Transformations MPG – chapter 21
- Camera and Projection MPG – chapter 9
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5.12, 5.13, 6-8, 14

Camera

- Idealized camera (pin-hole)
 - Idealized geometric optics
 - Realistic effects as post process
- Camera description
 - Explicit parameters (position, orientation)
 - Node in a scene graph
 - Other parameters – viewing angle, viewport, rendering setup, ...
- Series of transformations
 - Viewing transformation (camera position / orientation)
 - Projection transformation (viewing volume)
 - Viewport transformation (viewport on the screen)
 - Composed with the modeling transformation

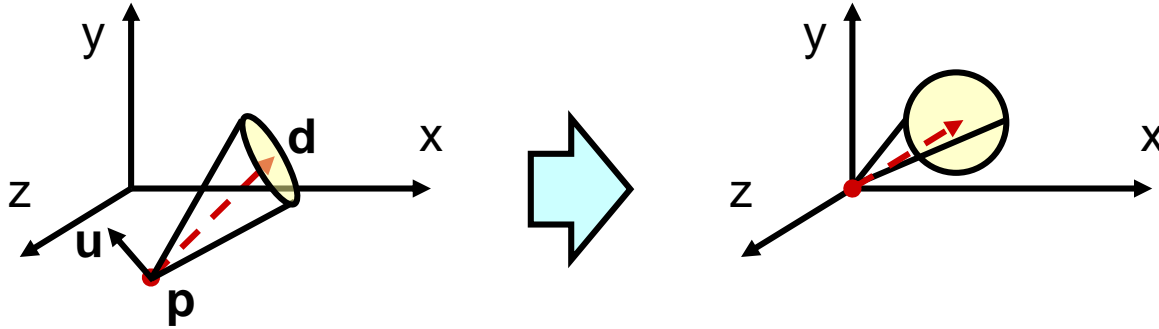
Rendering Pipeline

- 1. part – transformations (*viewing pipeline*)
- 2. part – further operations



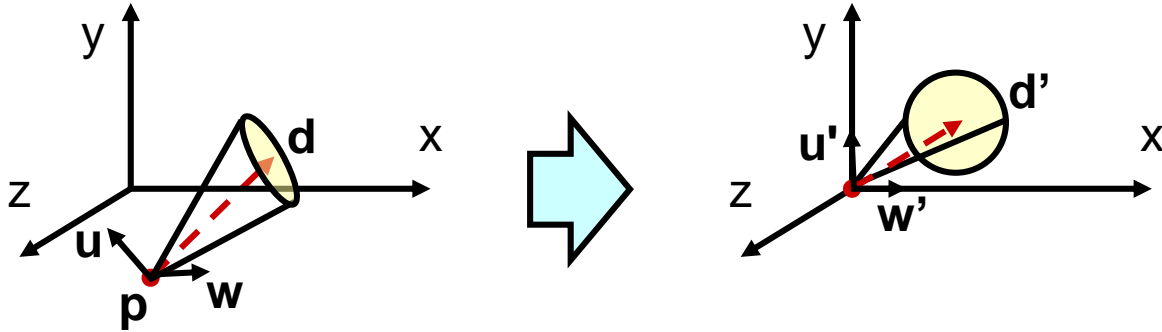
View transformation

- Transformation of scene to unified position



- Camera position p** to $[0,0,0]$... translation
- View direction d** // with z axis ... rotation
- Up vector u** // with y axis ... rotation around z axis
- Camera matrix M : Viewing transformation = M^{-1}

View transformation matrix

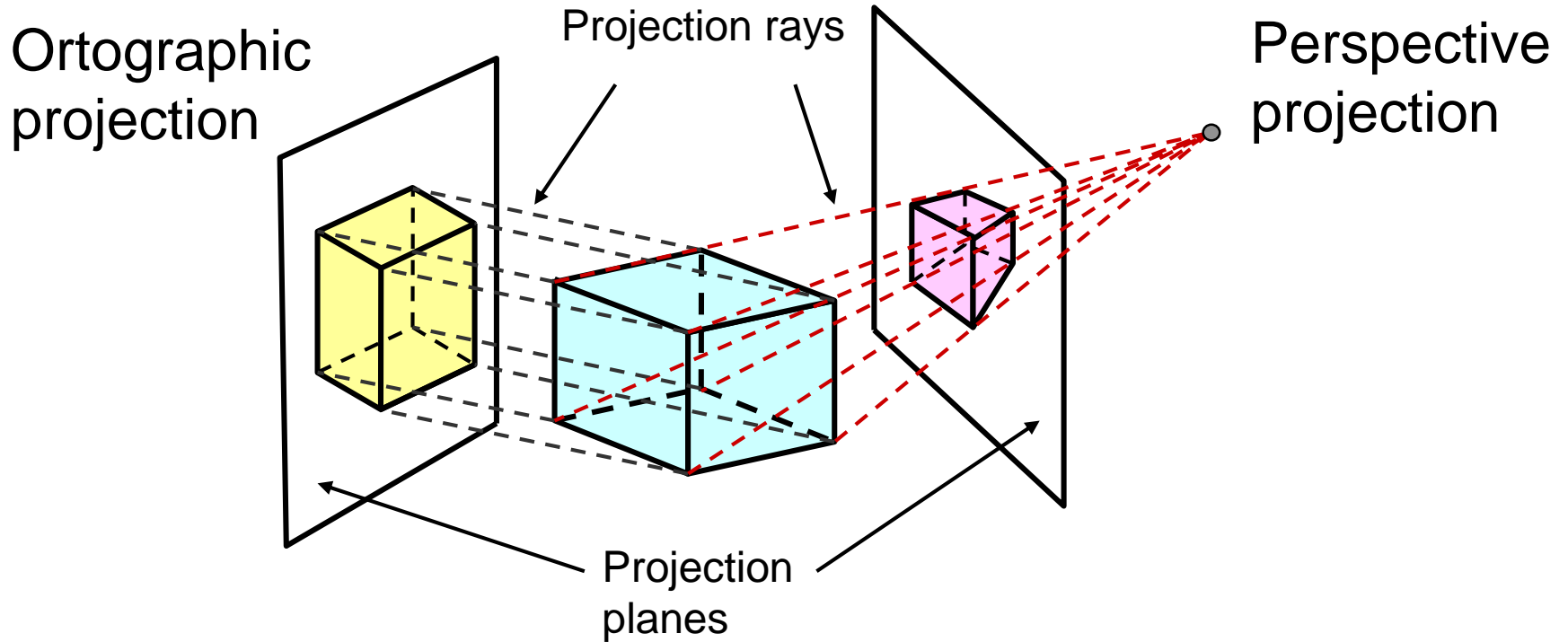


- $M_V = M_C^{-1}$ (M_C camera matrix)

$$w = d \times u$$

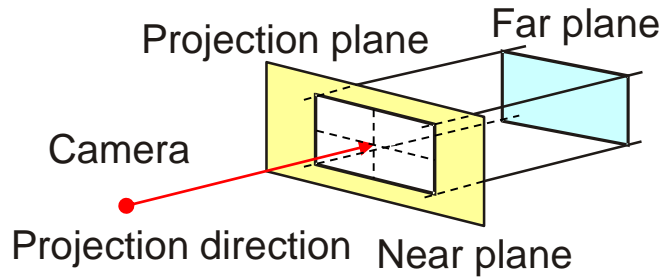
$$M_V = \begin{bmatrix} w_x & u_x & d_x & p_x \\ w_y & u_y & d_y & p_y \\ w_z & u_z & d_z & p_z \\ 0 & 0 & 0 & 1 \end{bmatrix}^{-1}$$

Orthographic and perspective projection

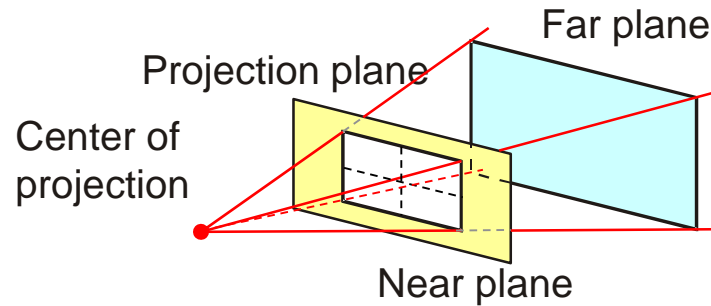


Camera – projection transformation

- Transformation from 3D space to 2D projection plane
- *Viewing volume / frustum (záběr)*



Orthographic projection
view volume = cuboid

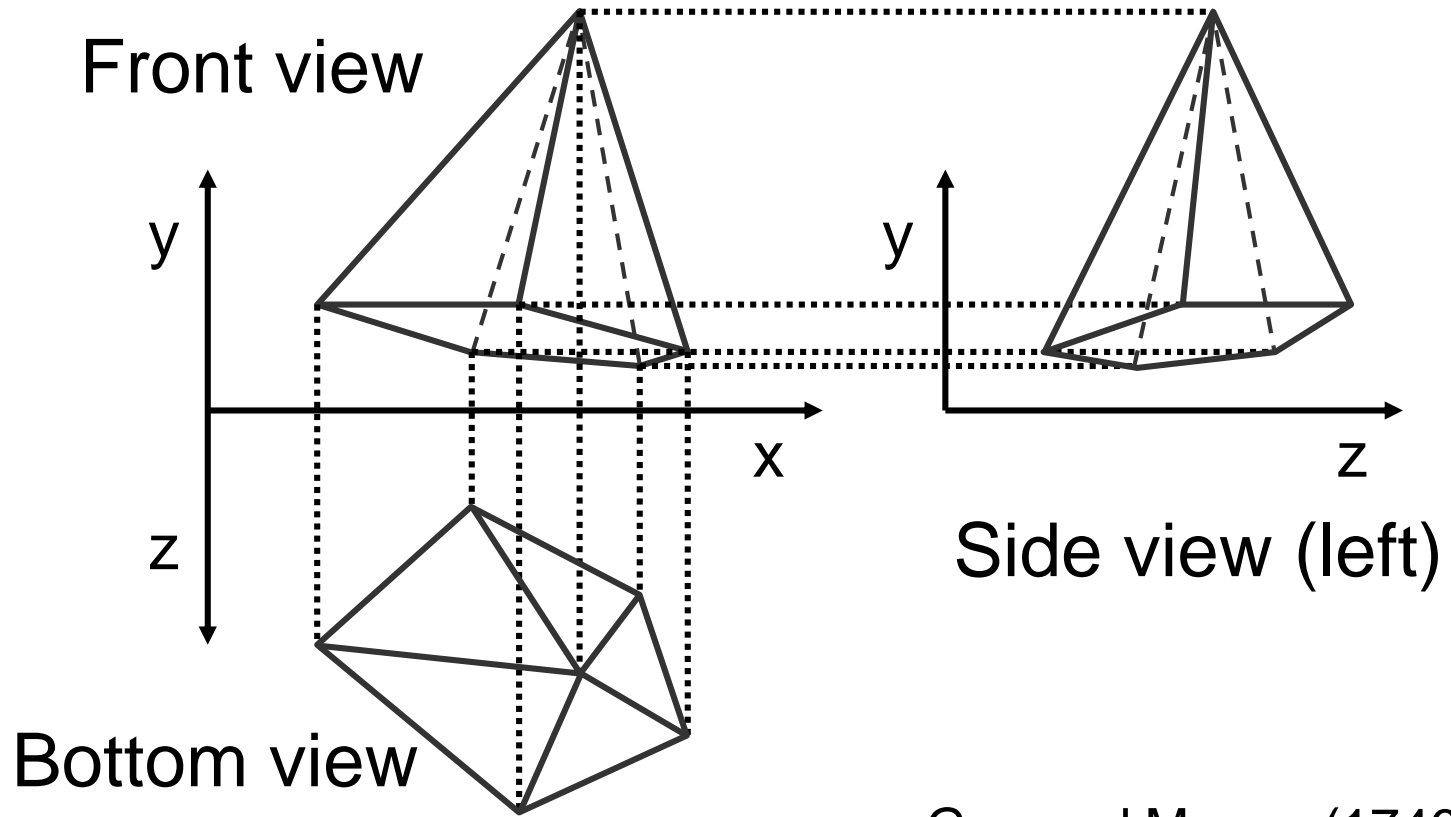


Perspective projection
view volume = pyramid frustum

Orthographic Projection

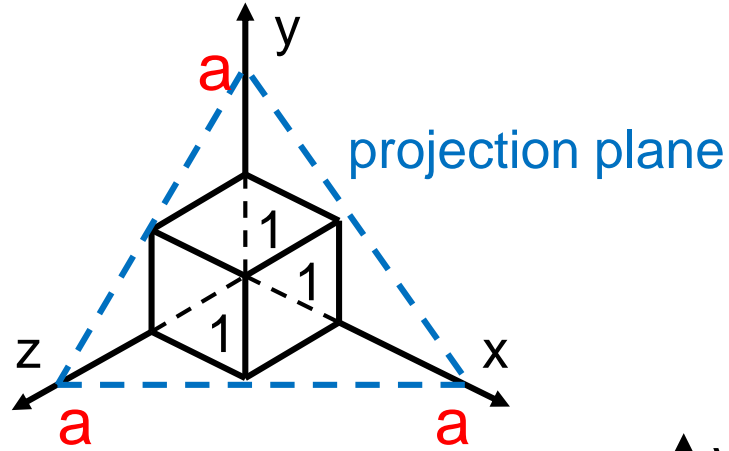
- All rays parallel!
- Rays **orthogonal** to projection plane
 - Monge's projection: top, front, side
 - Axonometry (arbitrary projection plane)
- Rays **non-orthogonal** to projection plane (oblique projection)
 - Cavalier projection (the same scale on axes)
 - Cabinet projection (z axis scale = 1/2)

Monge's projection

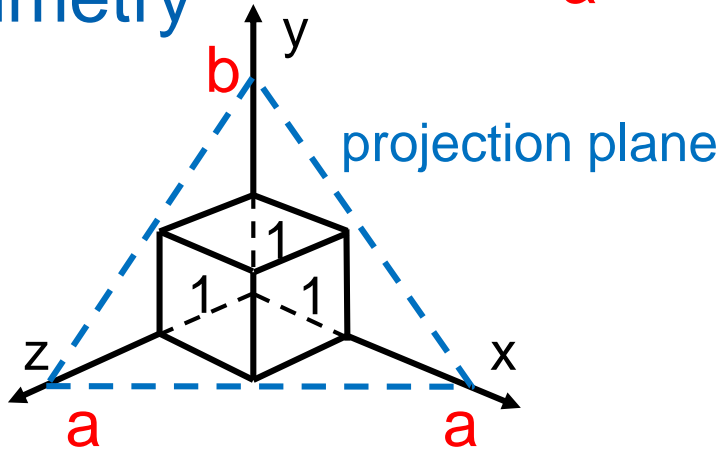


Axonometry

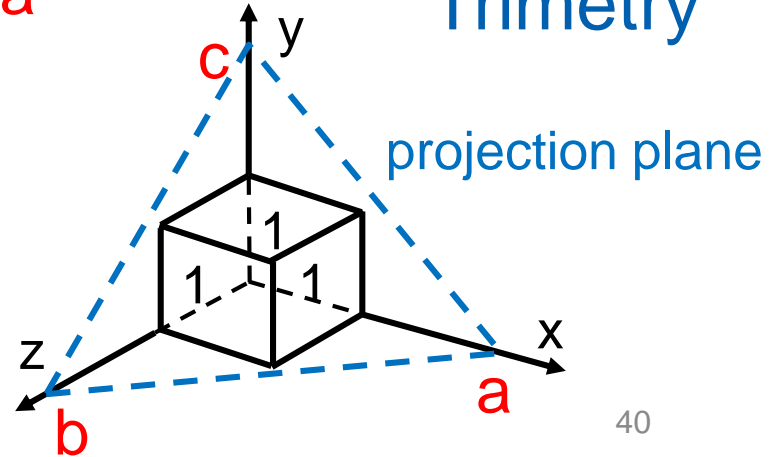
Isometry



Dimetry

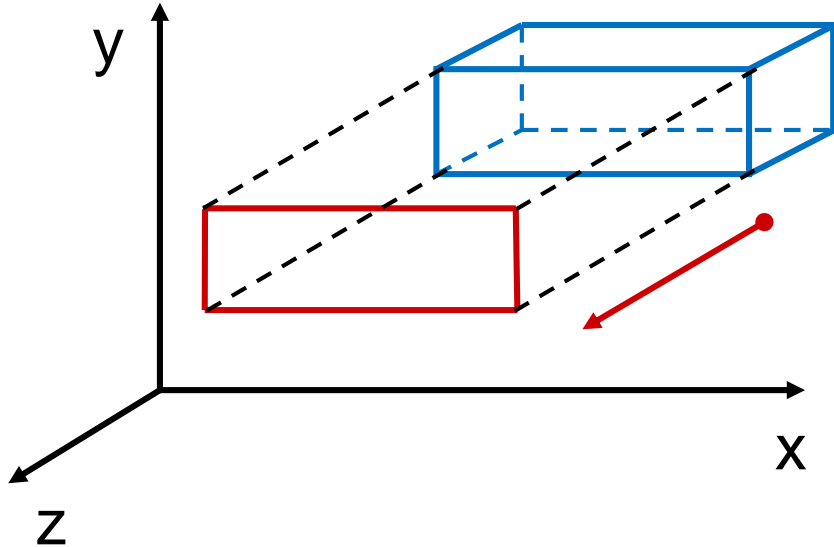


Trimetry



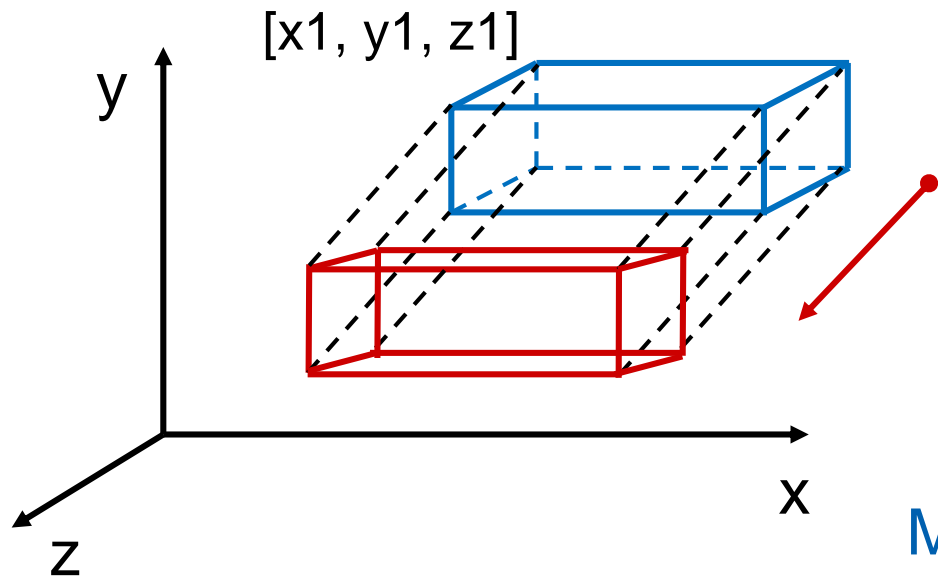
Projection: Matrix Form

- Align projection direction to z axis (rotation)
- Projection plane = xy



$$M_{//} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Oblique Projection



$$\begin{aligned}x &= x_1 + x_p \cdot t \\y &= y_1 + y_p \cdot t \\z &= z_1 + z_p \cdot t\end{aligned}$$

$$z = 0 \Rightarrow t = -z_1 / z_p$$

Projection direction $[x_p, y_p, z_p]$

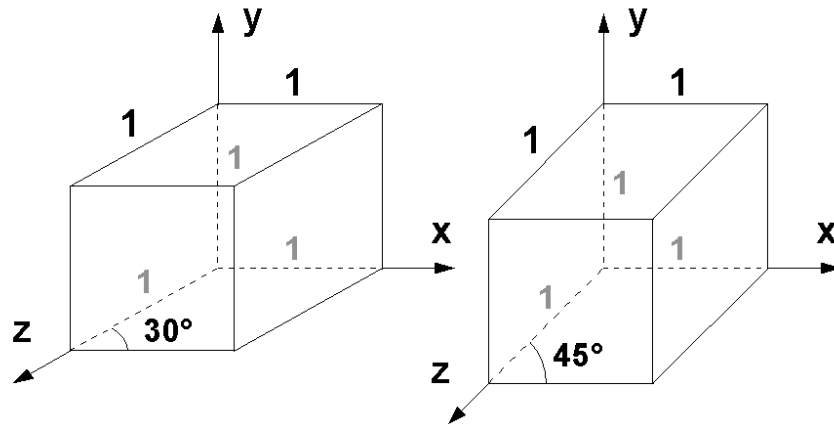
$$M = \begin{bmatrix} 1 & 0 & -\frac{x_p}{z_p} & 0 \\ 0 & 1 & -\frac{y_p}{z_p} & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$M = M_{//} \cdot M_{zk}$$

Oblique Projection

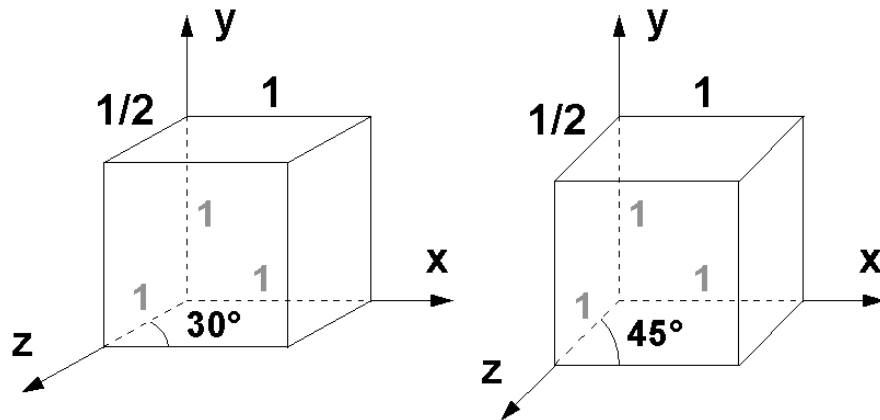
Cavalier

$$M = \begin{bmatrix} 1 & 0 & -\cos \beta & 0 \\ 0 & 1 & -\sin \beta & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

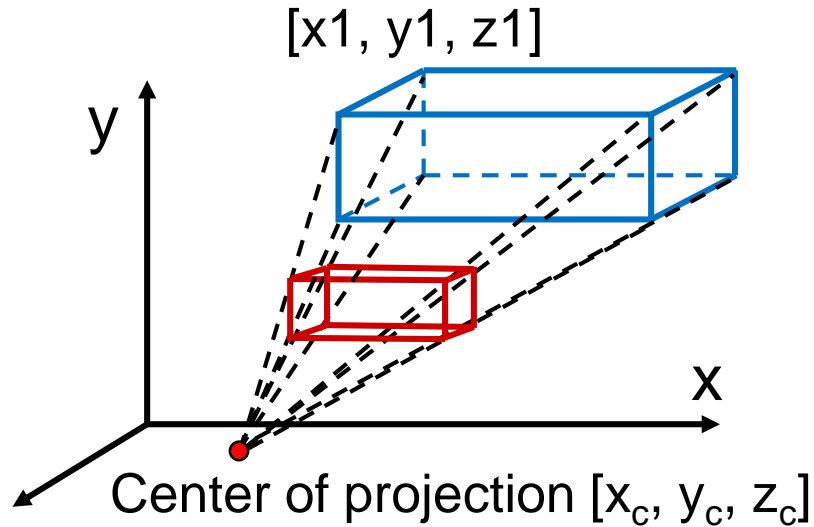


Cabinet

$$M = \begin{bmatrix} 1 & 0 & \frac{-\cos \beta}{2} & 0 \\ 0 & 1 & \frac{-\sin \beta}{2} & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$



Perspective Projection



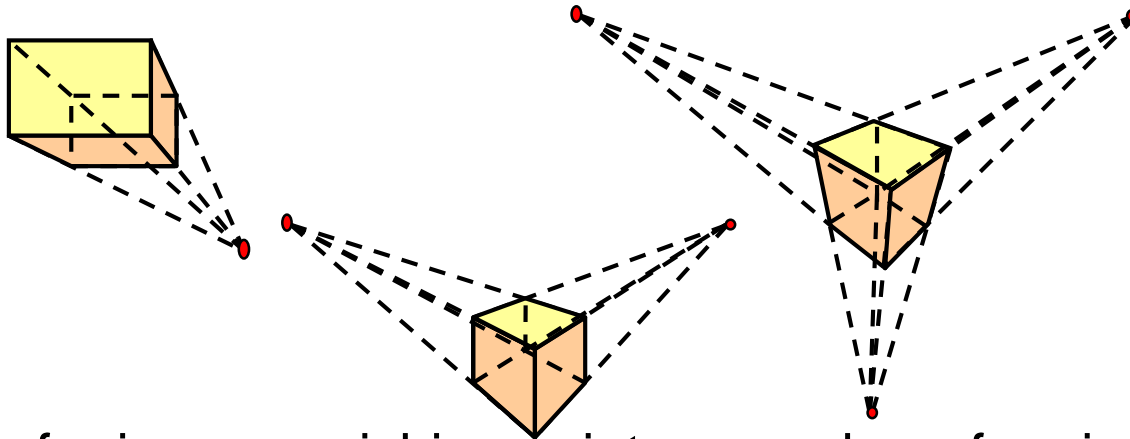
$$\begin{aligned}x &= x_c + (x_1 - x_c) \cdot t \\y &= y_c + (y_1 - y_c) \cdot t \\z &= z_c + (z_1 - z_c) \cdot t\end{aligned}$$

$$z = 0 \Rightarrow t = z_c / (z_c - z_1)$$

$$M = \begin{bmatrix} 1 & 0 & -\frac{x_c}{z_c} & 0 \\ 0 & 1 & -\frac{y_c}{z_c} & 0 \\ 0 & 0 & \frac{z_c}{z_c} & 0 \\ 0 & 0 & -\frac{1}{z_c} & 1 \end{bmatrix}$$

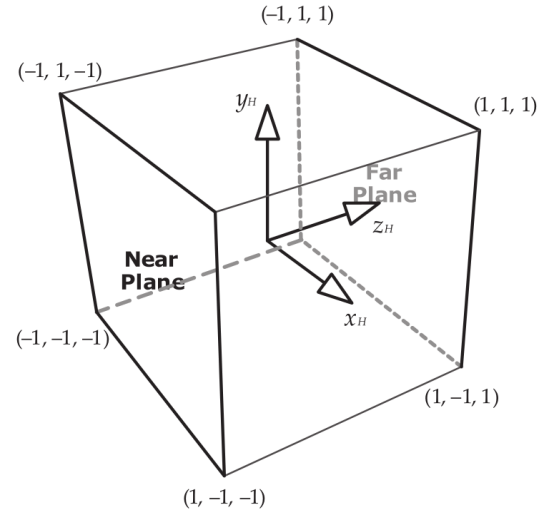
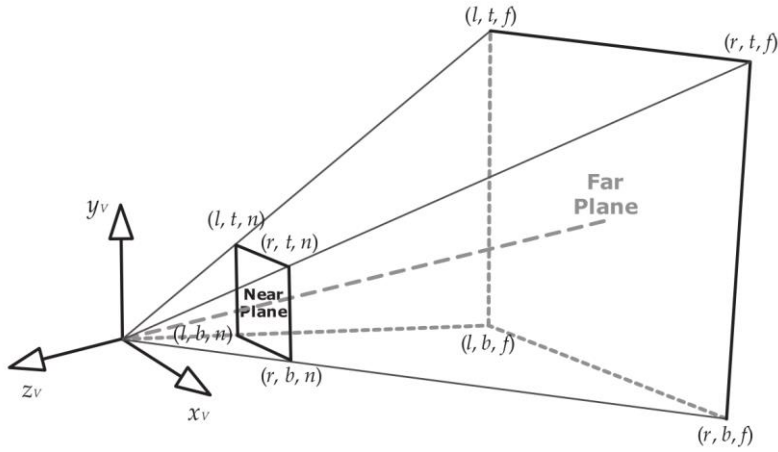
Vanishing Points (Úběžníky)

- Perspective projection does not keep parallelism
- Lines parallel to coordinate axes meet in **primary vanishing points**
 - 1-, 2-, 3-point perspective



- Number of primary vanishing points = number of projection plane intersections with coordinate axes

Perspective Projection (OpenGL)

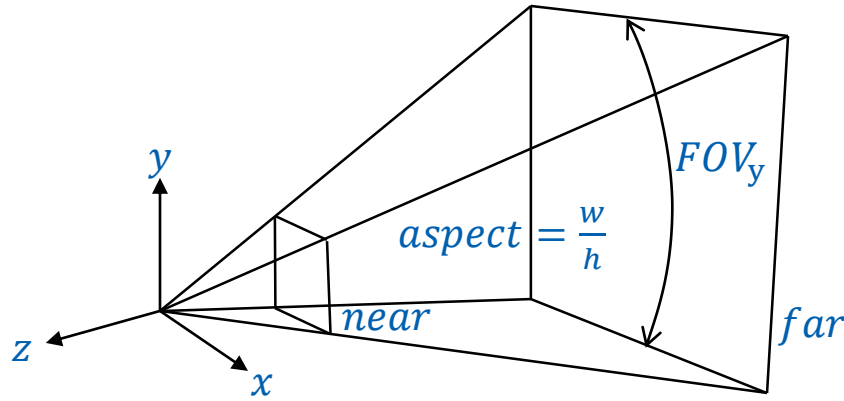


camera / eye space

$$P = \begin{bmatrix} \frac{2n}{r-l} & 0 & \frac{r+l}{r-l} & 0 \\ 0 & \frac{2n}{t-b} & \frac{t+b}{t-b} & 0 \\ 0 & 0 & -\frac{f+n}{f-n} & -\frac{2nf}{f-n} \\ 0 & 0 & -1 & 0 \end{bmatrix}$$

NDC / clip space

Symmetrical Perspective Projection



$$P = \begin{bmatrix} \frac{\cotg \frac{FOV_y}{2}}{aspect} & 0 & 0 & 0 \\ 0 & \cotg \frac{FOV_y}{2} & 0 & 0 \\ 0 & 0 & -\frac{f+n}{f-n} & -\frac{2nf}{f-n} \\ 0 & 0 & -1 & 0 \end{bmatrix}$$

Camera – Viewport Transformation

- Size and position of the viewport

$$x' = (x_{\text{NDC}} + 1) \frac{W}{2} + X$$

$$y' = (y_{\text{NDC}} + 1) \frac{H}{2} + Y$$

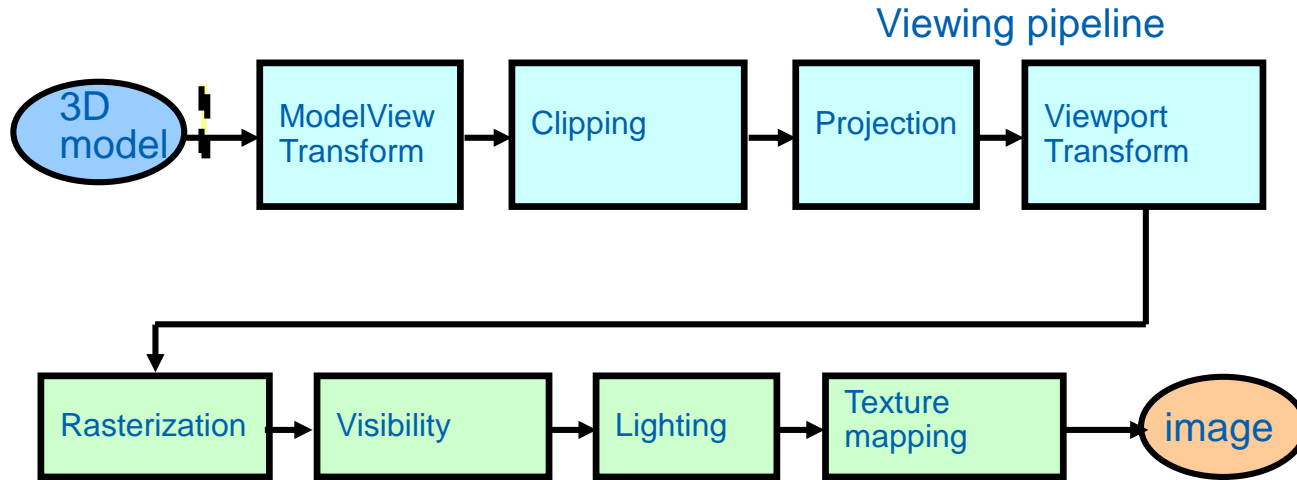
- x_{NDC} and y_{NDC} result of previous transf. (range -1..1)

Coordinate systems overview

- Object / Modeling / Local coordinates
 - Relative to object origin
- World coordinates
 - Global scene coordinates
- Camera / Eye / View coordinates
 - Camera in the origin, looks along $-z$
- Clip coordinates
 - After multiplication by projection matrix
- Normalized device coordinates
 - Cuboid after perspective division $[-1,-1,-1] - [1,1,1]$
- Screen / Window coordinates
 - x, y pixel position, z in $0..1$ range

Rendering Pipeline

- 1. part – transformations (*viewing pipeline*)
- 2. part – further operations



Outline

- Points, Vectors, Transformations MPG – chapter 21
- Camera and Projection MPG – chapter 9
- 3D Scene Representation MPG - chapters
5.11, 5.12, 5.13, 6-8, 14

Introduction to 3D geometry

- Scene = mathematical model of *the world* in computer
 - Rendering
 - Animation
 - Colisions
 - ...
- Geometry (3D models)
- Materials
- Lights
- Camera
- ...



3D Models

- Boundary representation (B-rep)
- Volumetric representation
- Constructive solid geometry (CSG)
- Implicit surfaces
- Point clouds
- ...

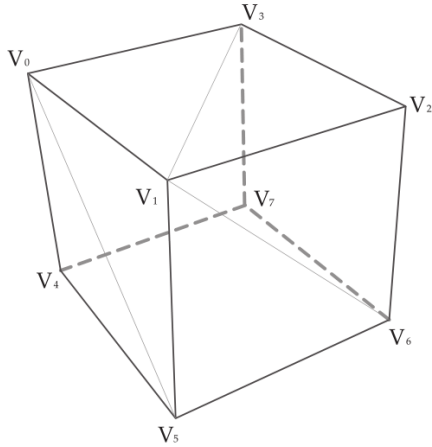
Polygonal Mesh

- Classical boundary representation
- Describes object surface (vertices, edges, faces)
- List of polygons defining object boundary (surface)
 - Better convex polygons
 - Even better just triangles (triangulation)
- Different representations
 - Sequence of vertices (separator)
 - Vertex array + index array
 - ...

Triangle Mesh

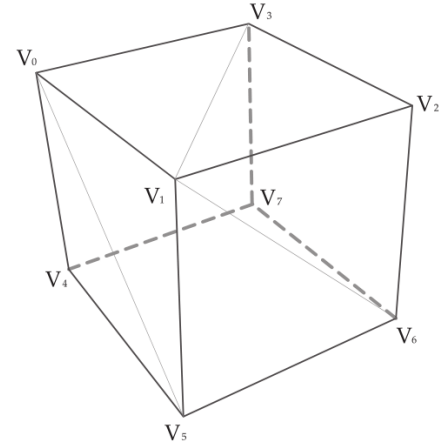
- Just triangles
 - HW friendly !
 - Simplified rendering, clipping, collisions, ...
- Mathematics of a triangle
 - In visibility / ray intersection lecture...

Triangle Mesh



V ₀	V ₁	V ₃	V ₁	V ₂	V ₃	V ₀	V ₅	V ₁	...	V ₅	V ₇	V ₆
----------------	----------------	----------------	----------------	----------------	----------------	----------------	----------------	----------------	-----	----------------	----------------	----------------

triangle list



Vertices

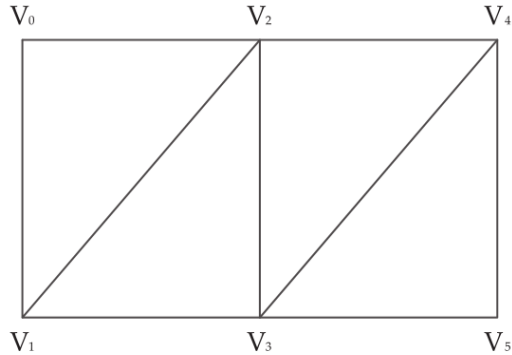
V ₀	V ₁	V ₂	V ₃	V ₄	V ₅	V ₆	V ₇
----------------	----------------	----------------	----------------	----------------	----------------	----------------	----------------

Indices

0	1	3	1	2	3	0	5	1	...	5	7	6
---	---	---	---	---	---	---	---	---	-----	---	---	---

indexed triangle list

Triangle Mesh – Compact Representation



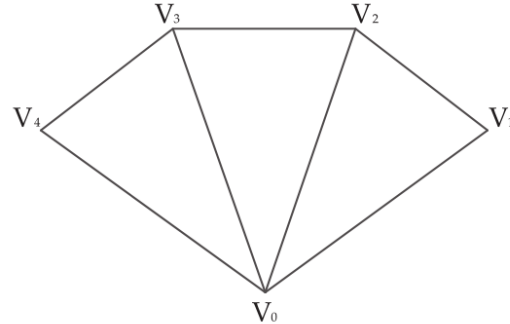
Vertices

V ₀	V ₁	V ₂	V ₃	V ₄	V ₅
----------------	----------------	----------------	----------------	----------------	----------------

Interpreted as triangles:

0 1 2	1 3 2	2 3 4	3 5 4
-------	-------	-------	-------

triangle strip



Vertices

V ₀	V ₁	V ₂	V ₃	V ₄
----------------	----------------	----------------	----------------	----------------

Interpreted as triangles:

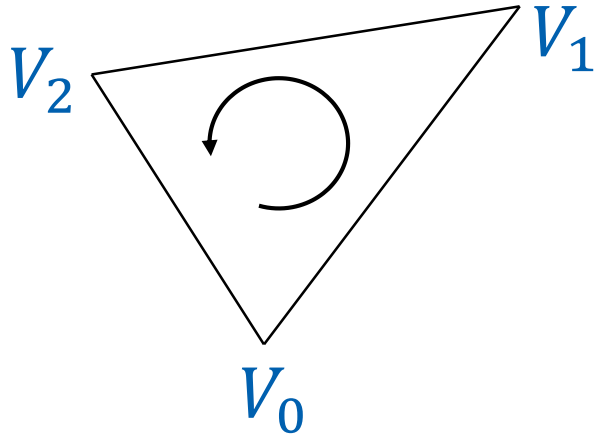
0 1 2	0 2 3	0 3 4
-------	-------	-------

triangle fan

No indices – saves memory!

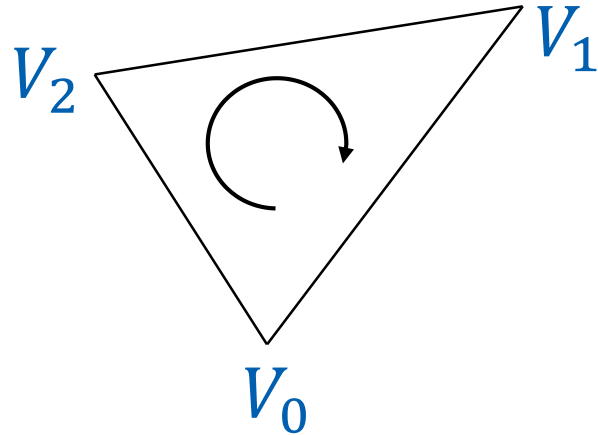
Triangle Mesh – Winding Order

- Defining front and back faces



$V_0V_1V_2$

CCW (counter clock wise)



$V_0V_2V_1$

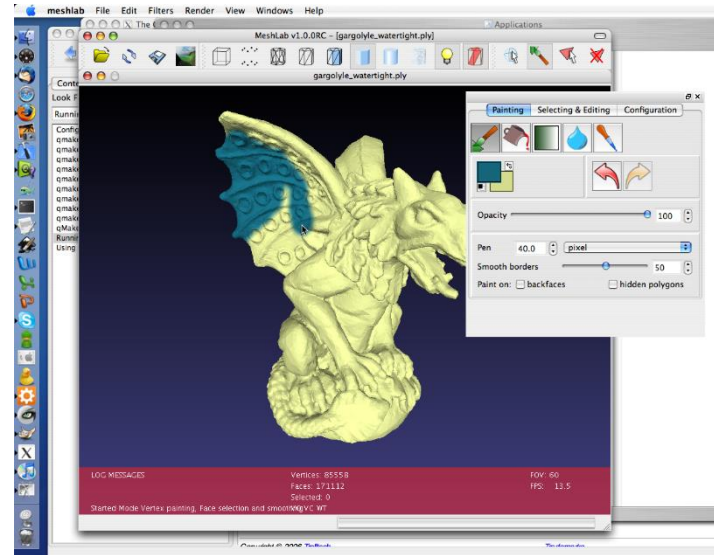
CW (clock wise)

Storing Other Information

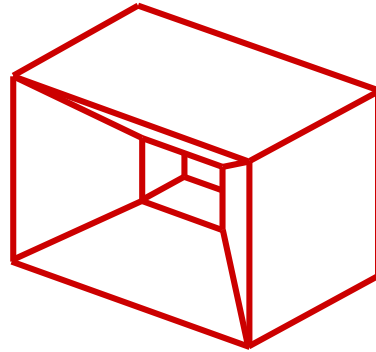
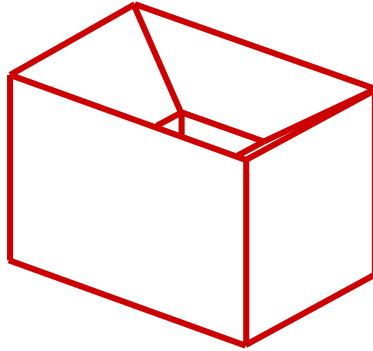
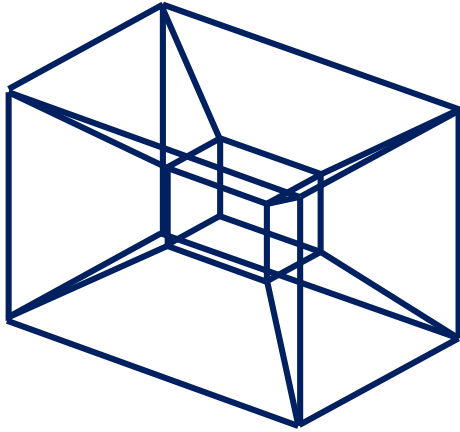
- Vertices
 - Position, normal, texture coordinates, color, ...
- Edges
 - sharp, auxiliary
- Faces
 - normal, material
- Solids
 - material, texture

Triangle Mesh

- Modeling
 - Maya, 3DS Max, Blender, Cinema
- Editing / Optimization
 - MeshLab
 - NvTriStrip
 - ...



Wireframe Model

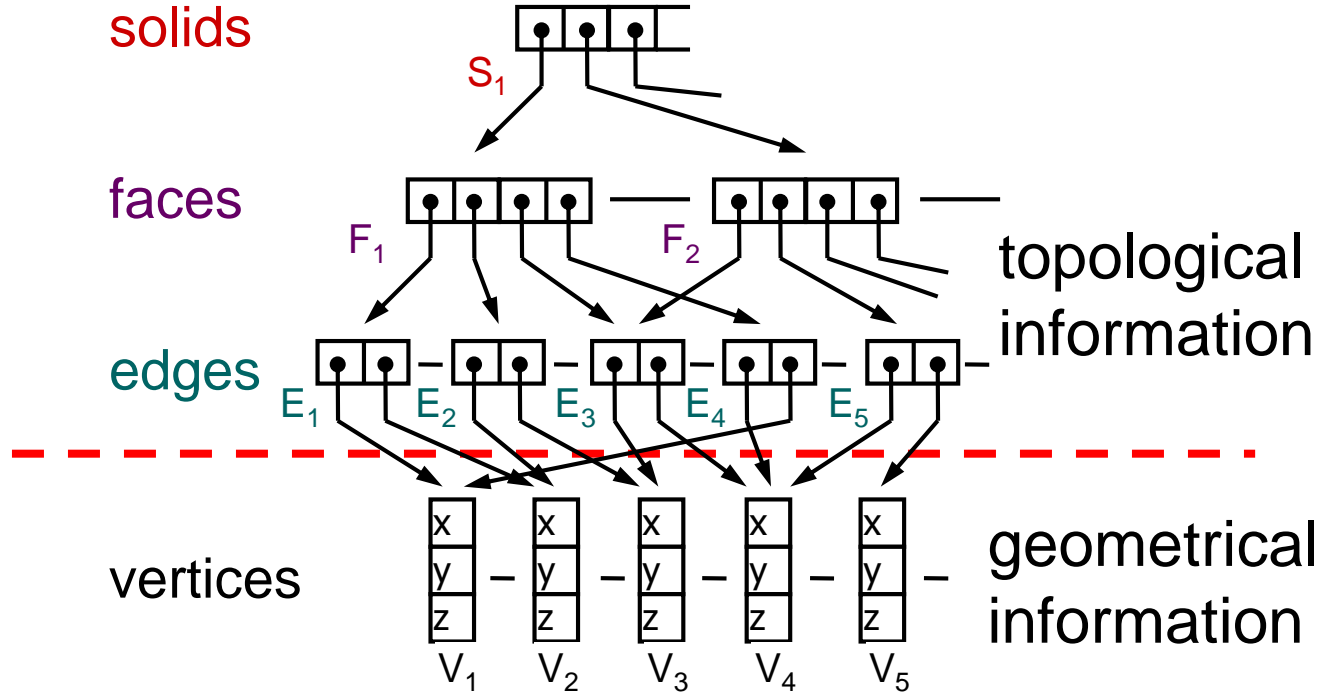


Ambiguous interpretation

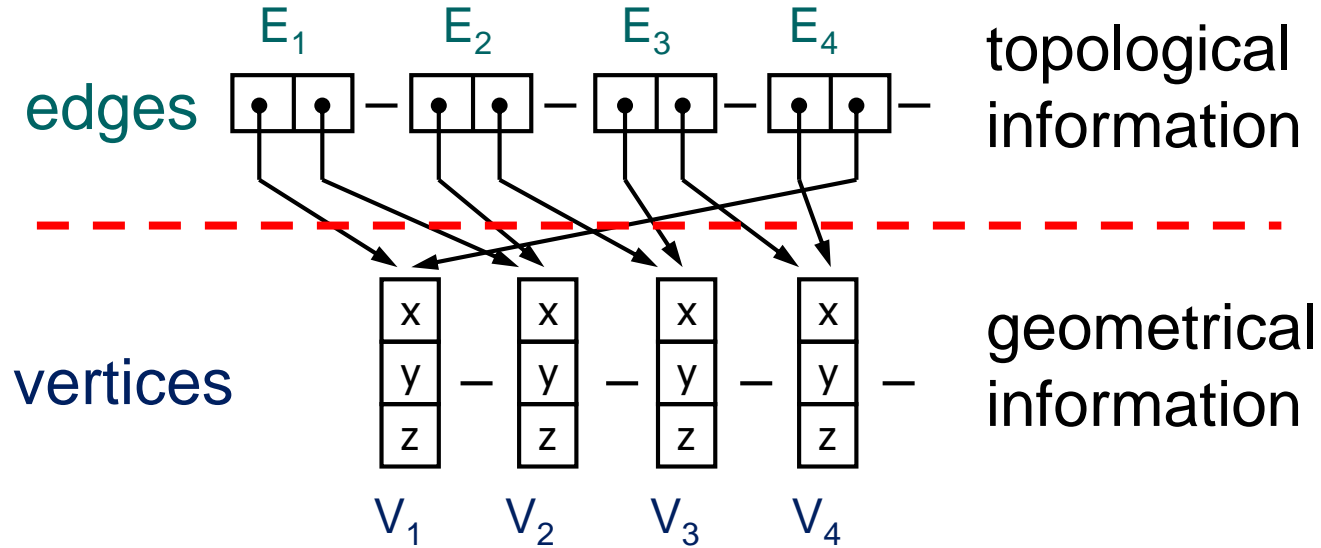
But very useful
for debugging!

Mesh Graph

Hierarchical representation

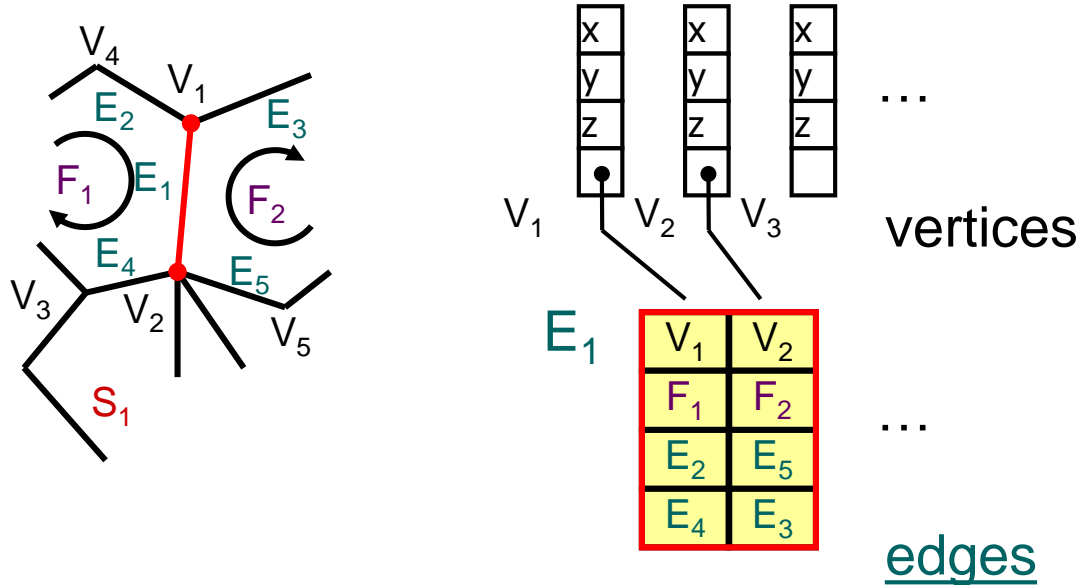


Wireframe Model



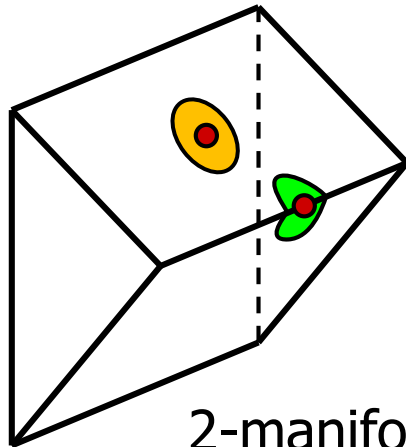
Winged-Edge

- Information about the neighborhood
- Useful for **editing & maintaining consistency**

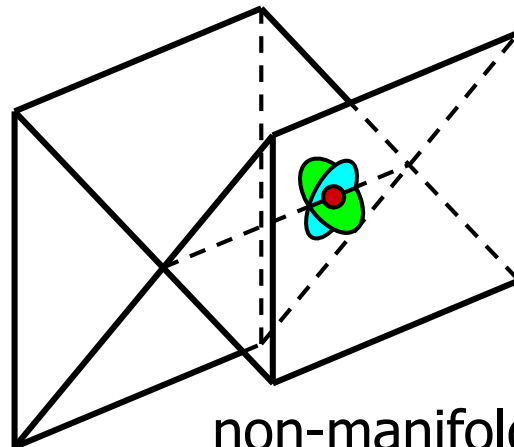


Model Unambiguity

- 2-manifold: for every surface point there is a neighborhood topologically equivalent with plane
- Important for manufacturing, CAD/CAM



2-manifold

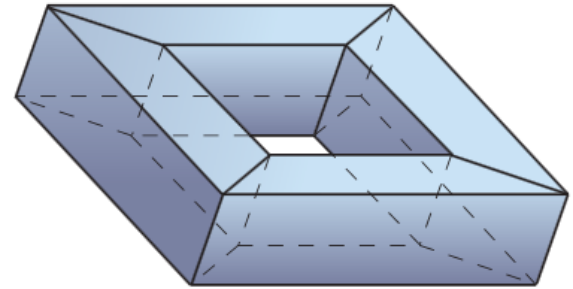


non-manifold

Euler-Poincare Formula for Manifolds

$$V - E + F - R = 2(S - H)$$

- V #vertices
- E #edges
- F #faces
- R #rings (holes in faces)
- H #holes (holes through object)
- S #shells (separate objects)



$$V=16$$

$$E=32$$

$$F=16$$

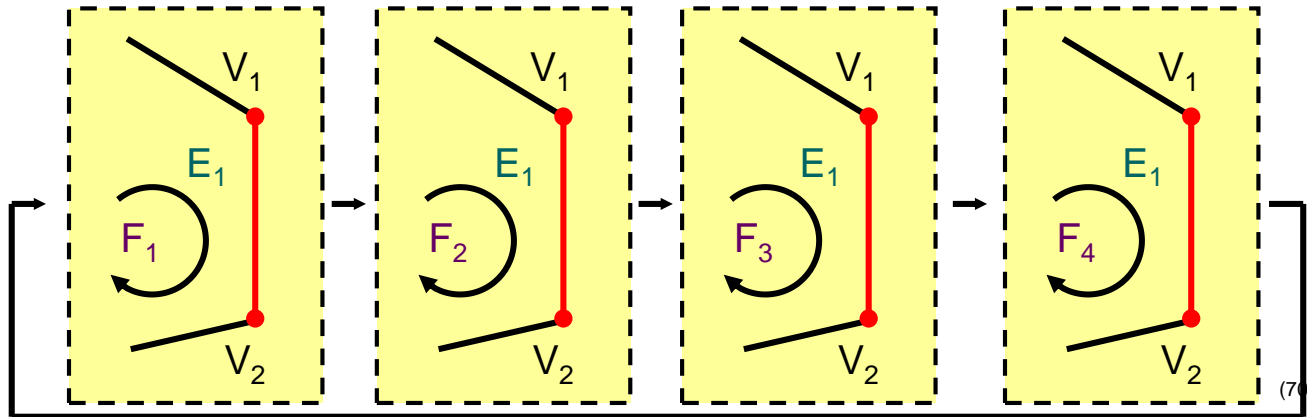
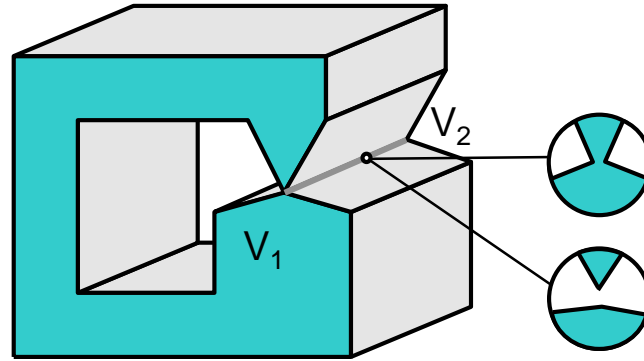
$$R=0$$

$$H=1$$

$$S=1$$

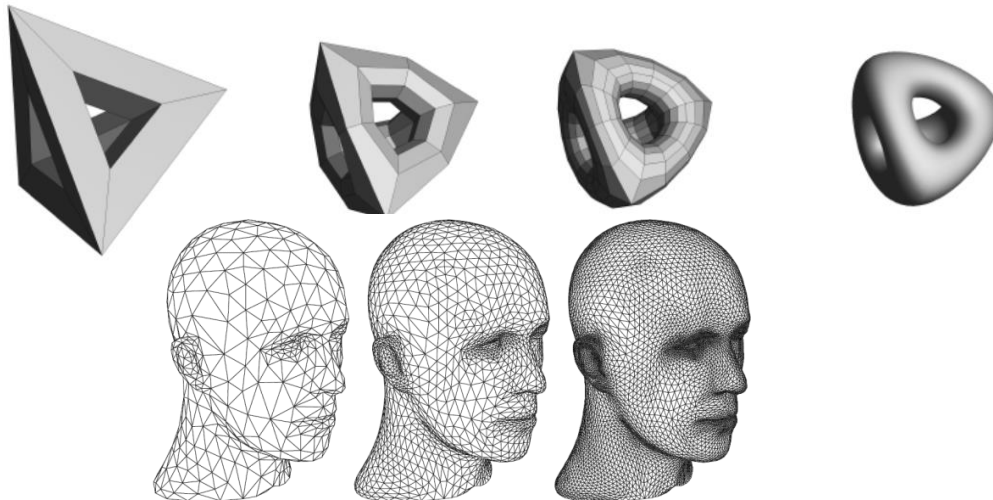
Representing non-manifolds

- Winged-edge: only manifolds
- Winged half-edge



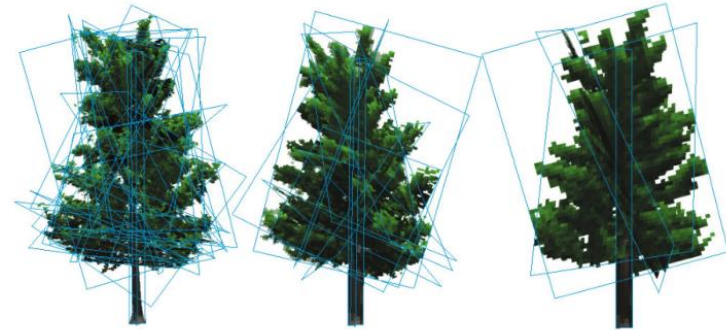
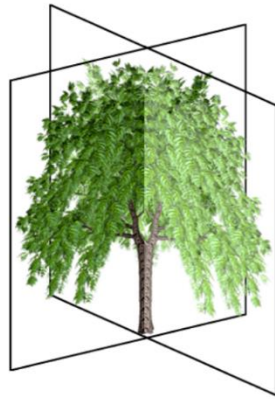
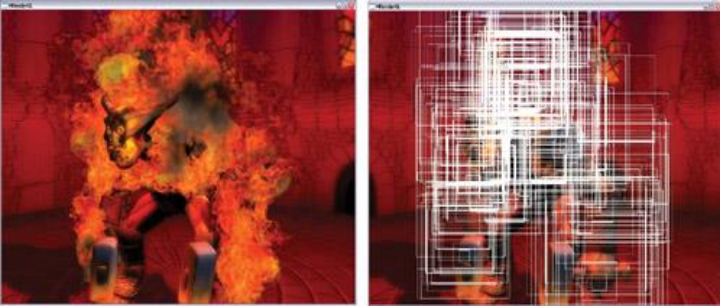
Subdivision Surfaces

- Progressively subdivide coarse mesh
- Different subdivision schemes
 - Loop, Catmull-Clark, Doo-Sabin
 - HW support: hull+tessellation shaders



Sprites, Billboards

- Replacing geometry with images – sprites / billboards/ impostors
- Billboard: oriented sprite
 - towards a camera or based on object features ...



Other B-reps

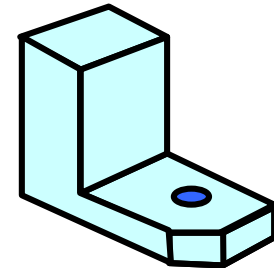
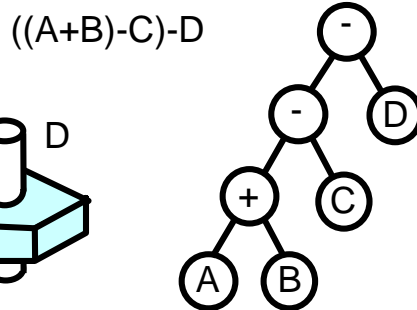
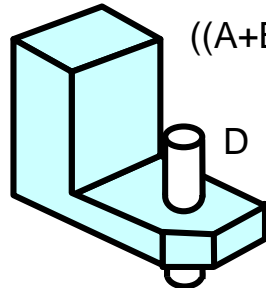
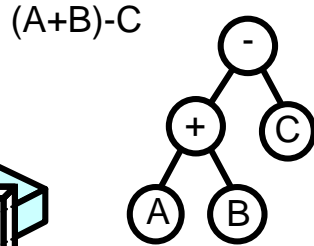
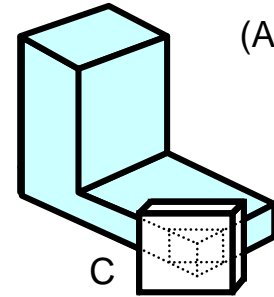
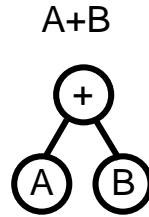
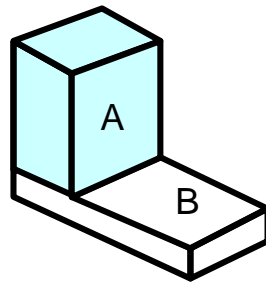
- Parametric surfaces
 - Bezier surface, Coons surface, NURBS
- Height fields
 - Regular / irregular
 - Terrains
- Impostors with depth
- LODs
 - Multiresolution representation

B-rep: Summary

- Easy (GPU) rendering
- Complicated operations on solids
 - No explicit information on what is the interior

CSG Tree

- Leaves: geometric primitives
- Inner nodes: set operations, transformations
- Root = model



CSG Tree - Properties

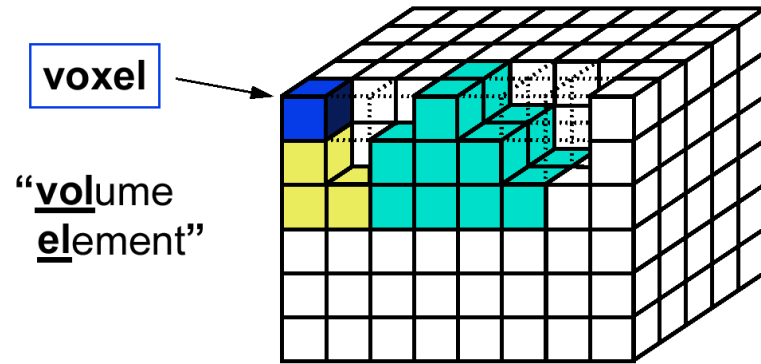
- Easy „point in solid“ test
- Modeling resembles manufacturing
 - Popular for 3D printing!
- Memory compact (primitives defined analytically)
- More complex rendering



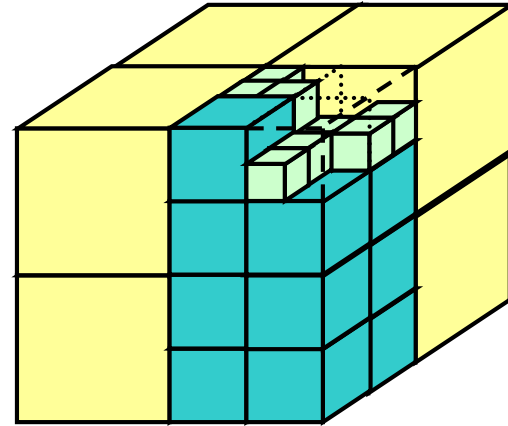
DP: Markéta Karaffová 2016

Volumetric representation

3D grid (regular structure)



Octree (hierarchical structure)



Volumetric rep.- properties

- Easy „point in solid“ test
- More difficult rendering (ray casting)



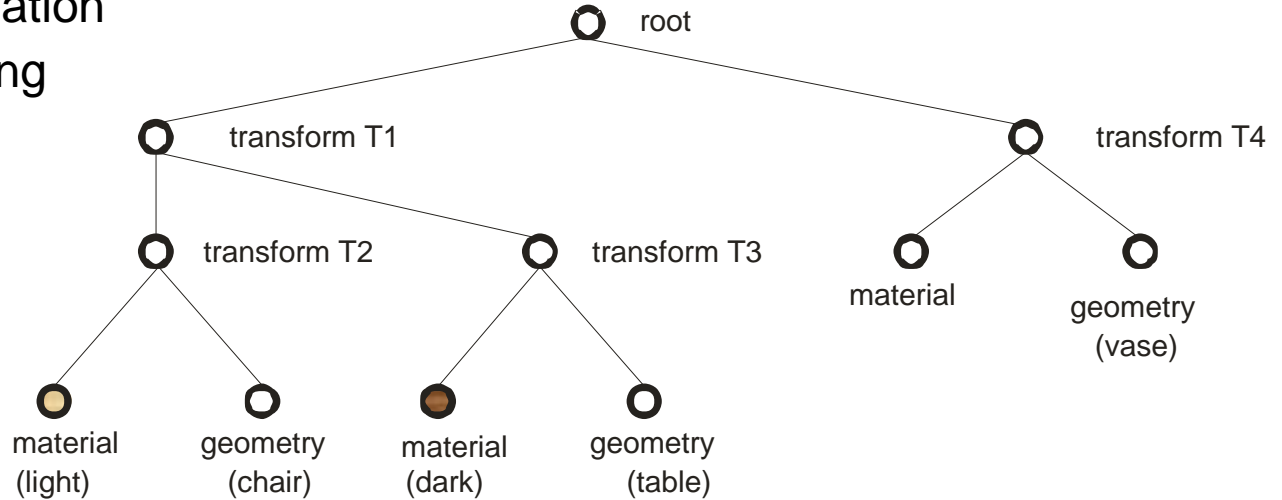
Source: Ikits et al. GPU Gems 2



DP: M. Benatsky 2011

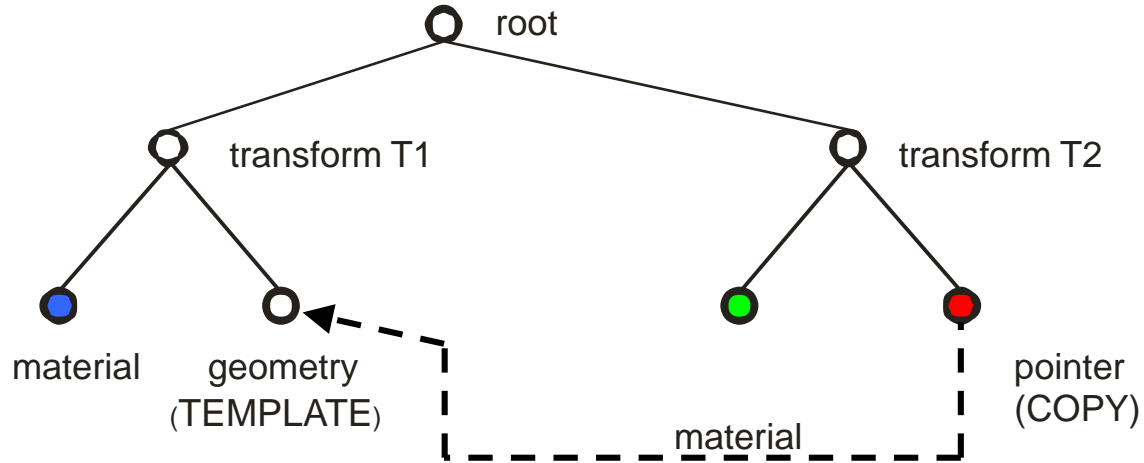
Scene Graph

- Logical / Semantical grouping
 - Transformation composition
 - Naming
 - Activation / deactivation
 - Partial spatial sorting



Scene graph - Instancing

- One Template / Many copies



- Saving memory, propagating changes
- Not a tree anymore: DAG!
 - Implications for a renderer

Summary

- Points, Vectors, Transformations MPG – chapter 21
- Camera and Projection MPG – chapter 9
- 3D Scene Representation MPG - chapters 5.11,
5.12, 5.13, 6-8, 14



DCGI

KATEDRA POČÍTAČOVÉ GRAFIKY A INTERAKCE

Questions?