Bounding Volumes
Bounding Volumes

Use simple volume

enclose object(s)

if ray doesn’t intersect volume
it doesn’t intersect what’s inside

tradeoff for rays where there is
extra intersection test for
  object intersections
  volume intersections, but not object intersections
v.
quick test for no intersection for no volume intersection
Bounding Volumes

3 approaches:

Bound object

Bound screen area that object projects to

Bound area of world space

Can use hierarchical organization of bounding volumes

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Bound Object

Easy-to-compute approximation to object

Easy to test for ray-bounding-object intersection

Trade-off complexity of computation v. tightness of fit

Can bound object in object space or world space
Axis Aligned Bounding Box

Easiest bounding volume to compute

Compute min/max for x, y, z of vertices

Some computational expense to test for intersection

Not tight fitting for some objects
Axis-Aligned Bounding box

limit[3][0] = 10000000000; limit[3][1] = -1000000000;
for each point, for each dimensions
    if p[i][j] < limit[j][0] then limitIndex[j][0] = i;
    if p[i][j] > limit[j][1] then limitIndex[j][1] = i;
Bounding Spheres

Takes some effort to compute optimal bounding sphere

Easy to compute approximation (non-optimal fit)

Easy to test for intersection (ray-sphere)

Not tight fitting for some objects
Bounding Spheres

Loop through points and record min/max in x, y, z

Use maximally separated pair of points and their midpoint as initial approximation to sphere

For each point in original set, adjust the bounding sphere to include the point
Bounding Spheres

\[
\text{limit}[3][0] = -10000000000; \quad \text{limit}[3][1] = 1000000000;
\]

for each point, for each dimensions

\[
\text{if } p[i][j] < \text{limit}[j][0] \text{ then } \text{limitIndex}[j][0] = i;
\]
\[
\text{if } p[i][j] > \text{limit}[j][1] \text{ then } \text{limitIndex}[j][1] = i;
\]
Bounding Spheres

k=0;
if (|limit[1][1]-limit[1][0]| > |limit[0][1]-limit[0][0]| ) k=1;
if (|limit[2][1]-limit[2][0]| > |limit[k][1]-limit[k][0]| ) k=2;
midpoint = (p[limit[k]]+p[limit[k]])/2;
radius = (p[limit[k]]-p[limit[k]])/2;
Bounding Spheres

• For each point
  – if \( p[i] \) is outside of radius of midpoint
  – \( \text{radius} = (\text{radius} + \text{dist(midpoint,} p[i]) \)/2 \)
  – \( \text{center} = p[i] + \text{radius} \times (\text{center} - p[i]) / |\text{center} - p[i]|; \)
Bounding Slabs

For each slab, user defines normal to use for slab pair

For each object, compute 2 d’s for each N

Takes some effort to compute d’s - how?

Takes some effort to test for intersection - how?

Can add more slabs to get tighter fit
Bounding Slabs
Bounding Slabs

SLAB: pair of parallel planes

for all points, compute $P \cdot N = d$

find min, max $d$ for all points
Bounding Slabs

Slab defined by: $N, d_1, d_2$

- ray defined by $P(t) = P + tD$
- intersection with plane: $N.P + t(N.D) = d$
- for each slab
  - retrieve $d_1, d_2, N$
  - compute
    - $t_1 = (d_1 - N.P)/(N.D); t_2 = (d_1 - N.P)/(N.D)$
    - keep track of entering max, exiting min
    - how to determine entering, exiting status?
Convex Hull

Smallest convex polyhedron containing object (point set)

Takes some effort to test for intersection - how?
Convex Hull

Find highest vertex
Find plane through vertex parallel to ground plane
Find second vertex that makes minimum angle with first vertex and up vector
Convex Hull

Find third vertex that makes plane whose normal makes minimum angle with up vector
Convex Hull

In the final convex hull, each edge will be shared by two and only two triangles.
For each unmatched edge (until there are no more), find vertex that, when a triangle is formed with the edge, will minimize angle between its normal and normal of shared face.
Hierarchical Bounding Volumes
Compute bounding volume for groups of objects

Compute bounding volume for groups of groups of objects
Test higher-level bound volumes first
Bound Area of Projection

Project object to picture plane

Bound columns and rows that object projects to

Only intersect first-level rays with pixels in projected area
i.e., only good for ray-casting part of ray-tracing
Bound Area of Projection

Project vertices onto picture plane

Find 2D bounding box on picture plane
Bound Area of Projection

Project rays through pixels inside bound

Only test object that was bounded
Areas of projection can be grouped hierarchically
Bound Area, not Object

In 2D - it looks like this:

Bucket sort objects into cells
Bound Area of 3D World

Divide world space into cells

Dump objects into cells: an object is dumped into each cell it touches
Bound Area of World

Trace ray through cells from closest to farthest
Intersect ray with each object in cell
Stop when it hits closest object in cell

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Bound Area of World

Traverse cells in order – test all objects in cell

If no intersections, step to next cell

If one or more intersections, get closest intersection
Bound Area of World

Use octree (quadtree in 2D)

Hierarchical approach: cells, then subcells...
Takes significant coding to keep track of level
Overhead in popping up and down in hierarchy

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Binary Spatial Partitioning