Computer Animation Algorithms and Techniques

Figure Animation

Rick Parent

Vitrual Human Representation

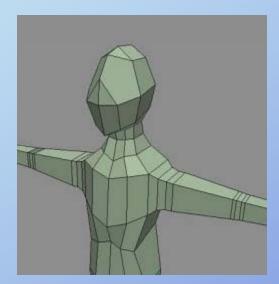
Body Modeling Geometric representation level of detail DoFs accessories: hair, clothes rigid v. flexible

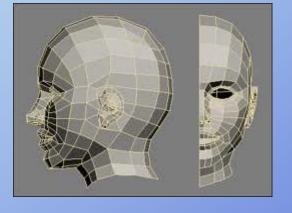
<u>Activities</u>

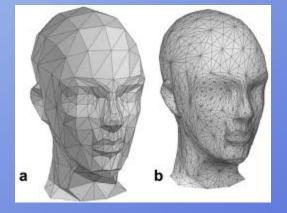
upper body tasks: reaching, grasping locomotion: walking, running body language: stance, gestures

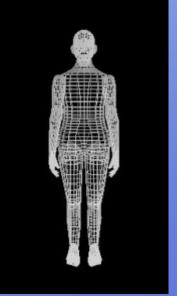
Secondary motion upper body tasks: reaching, grasping locomotion: walking, running body language: stance, gestures

Polygonal representations





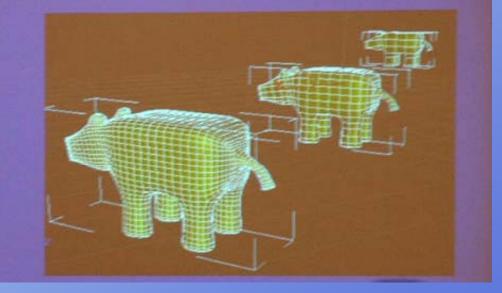




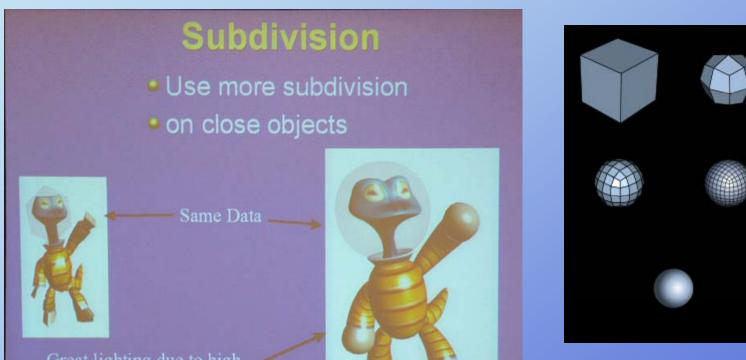
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Patches

- Patches are defined by 4*4 arrays of control points
- Arbitrary level of uniform subdivision



Subdivision surfaces

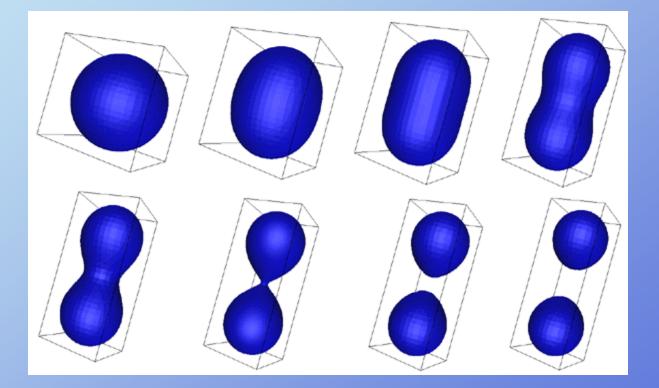


Levels of tessellation!

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Implicit surfaces



Body scan





http://www.cyberware.com/

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Animation- Rigid Links

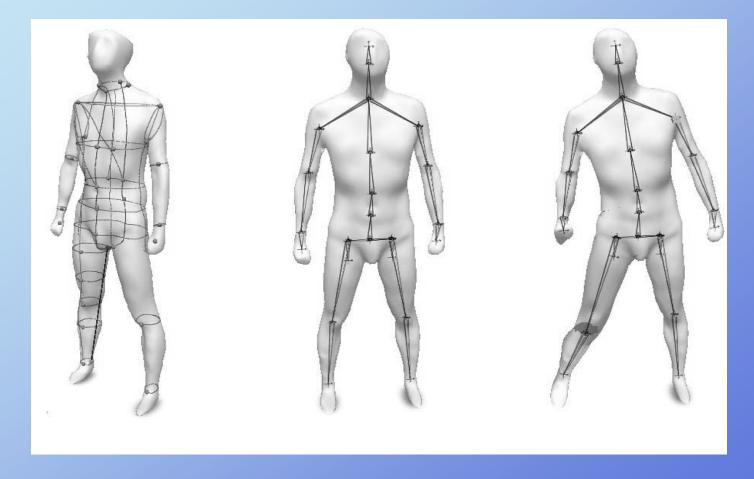


Hierarchical animation

Use FK or IK to animate

Interpolate between key frames

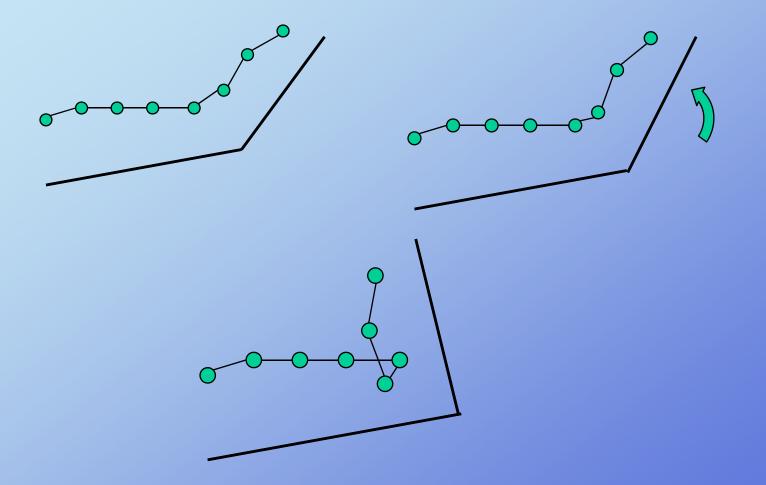
Animation - Skeleton Driven



http://www.emeraldinsight.com/journals.htm?articleid=1532798&show=html

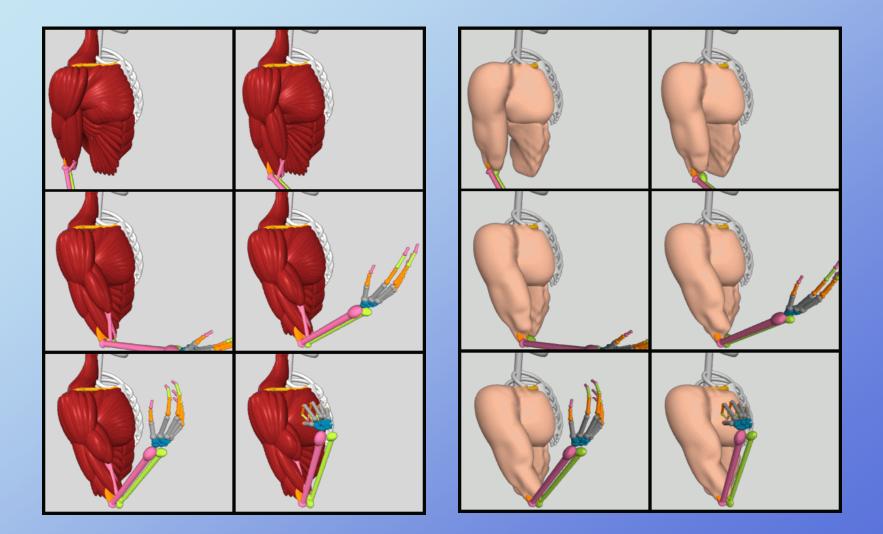
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Animation - Skeleton Driven



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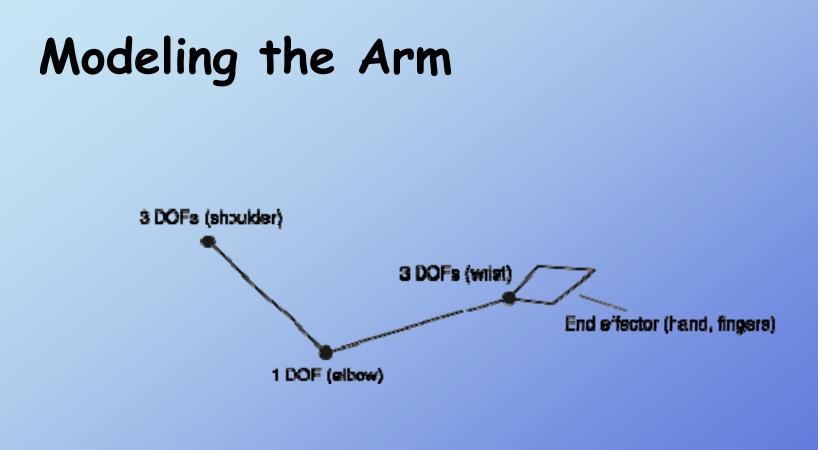
Animation-Layered Approach



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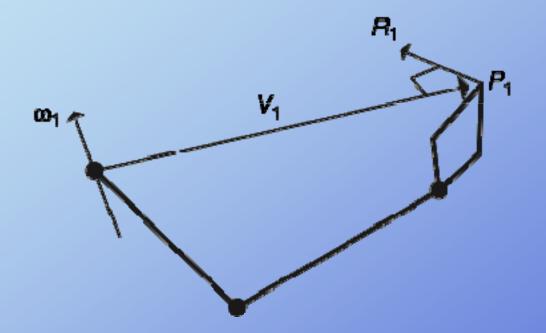
Reaching

Modeling the arm The shoulder joint The hand Coordinated movement Obstacles Strength



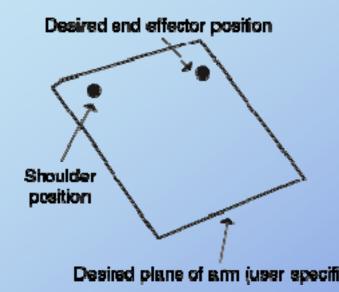
Also used is 3-2-2 DoF

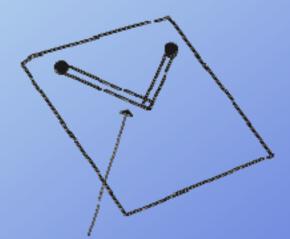
Modeling the Arm



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Modeling the Arm

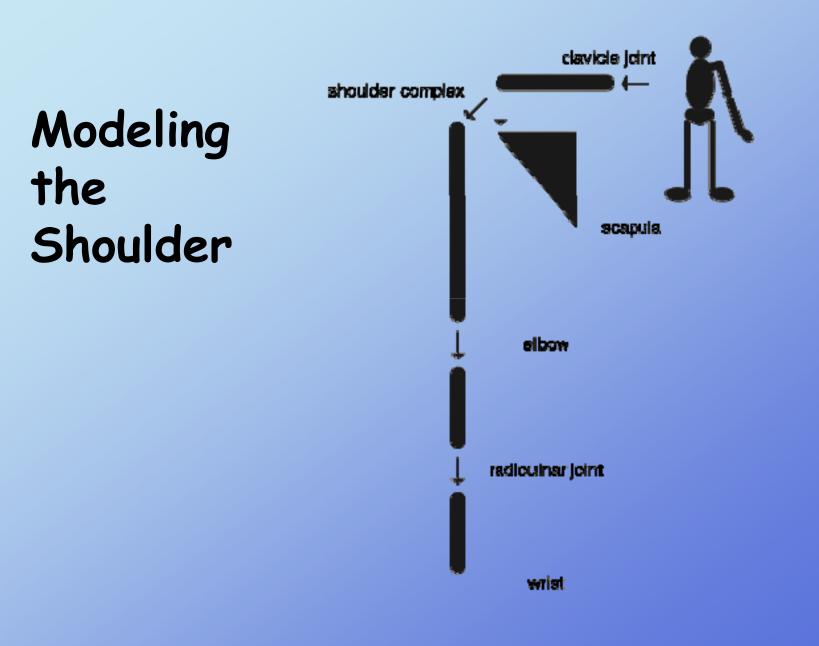




Desired plane of arm (user specified) Arm configuration constructed in the plane

Determine plane of motion (3 DoF) then 1-1 DoF arm Then 2/3 DoF wrist

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| Reaching 03 04 05 06 07 08 09 10 11 12 13 14 15 Values indicate potentials | | | | | | | | | | | | | | | | | |
|--|----|-----------|----|----|----|----|----|----|------------|----|----|----|-----|----|----|----|----------------------------|
| | 00 | -87 | | 03 | 04 | 05 | 09 | 07 | 08 | Q9 | 10 | 11 | 12 | 13 | 14 | 15 | Values indicate potentials |
| 00 | 30 | 30 | 30 | 29 | 28 | 27 | 26 | 28 | 29 | 30 | 31 | 32 | 33 | 3 | 38 | 38 | induced by obstacles |
| 01 | 30 | 26 | 25 | 24 | 23 | 22 | 21 | 22 | 23 | 24 | 25 | 28 | 27 | 28 | 29 | 38 | |
| 02 | 30 | 25 | 24 | 23 | 22 | 21 | 20 | 21 | 22 | 23 | 24 | 25 | 26 | 27 | 28 | 38 | |
| 03 | 29 | 24 | 23 | 24 | 28 | 28 | 19 | 20 | 21 | 22 | 25 | 28 | 27 | 28 | 29 | 34 | Polygons indicate |
| 04 | 29 | 23 | 22 | 28 | 28 | 19 | 18 | 19 | 20 | 29 | 30 | 31 | 32 | 34 | 30 | 34 | obstacles |
| 05 | 27 | <u>22</u> | 21 | 26 | 19 | 18 | 17 | 18 | 17 | 24 | 21 | 02 | 08 | * | 80 | 34 | Goal position for |
| 06 | 26 | 21 | 20 | 25 | 18 | 17 | 16 | 15 | 16 | 17 | 02 | 01 | 024 | 0 | 02 | 07 | end effector |
| 07 | 25 | 20 | 19 | 18 | 17 | 18 | 15 | 14 | 05 | 12 | 11 | 15 | 01 | 02 | 80 | 00 | |
| 08 | 24 | 19 | 18 | 17 | 18 | 15 | 14 | 13 | 12 | y | 10 | 05 | 04 | 03 | 04 | 00 | |
| 09 | 25 | 20 | 19 | 19 | 17 | 16 | 15 | 12 | 1 | 70 | 09 | 08 | 05 | 04 | 05 | 10 | |
| 10 | 25 | 21 | 20 | 19 | 18 | 16 | 12 | 13 | 12 | - | 06 | 07 | 06 | 05 | 08 | 15 | Selected key frames from |
| 11 | 25 | 25 | 25 | 24 | 23 | 18 | 15 | 14 | 13 | 12 | 09 | 08 | 09 | 10 | 11 | 16 | path of arm computed by |
| 12 | 26 | 26 | 28 | 25 | 24 | 17 | 18 | 13 | 1 6 | 22 | 12 | 11 | 10 | 11 | 12 | 17 | genetic algorithm |
| 13 | 27 | 22 | 21 | 20 | 19 | 18 | 17 | 18 | 17 | 18 | 13 | 12 | 11 | 12 | 18 | 18 | |
| 14 | 27 | 23 | 22 | 21 | 20 | 19 | 18 | ΰ. | 16 | 15 | 14 | 13 | 12 | 13 | 14 | 18 | - Initial configuration |
| 15 | 27 | 27 | 27 | 26 | 25 | 24 | 28 | 22 | 28 | 23 | 23 | 18 | 17 | 18 | 18 | 18 | ofarm |

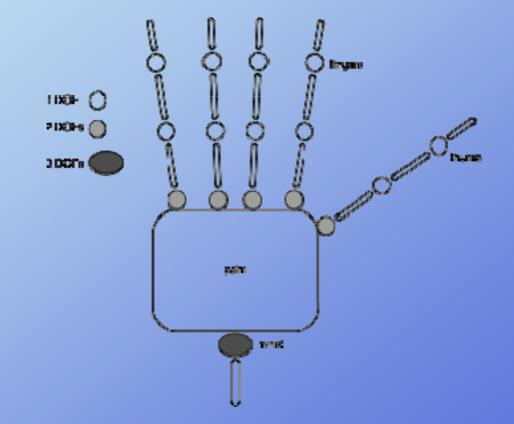


Approximating Human Reaching Volumes Using Inverse Kinematics I. Rodrígueza, M. Peinadoa, R. Boulicb, D. Meziata

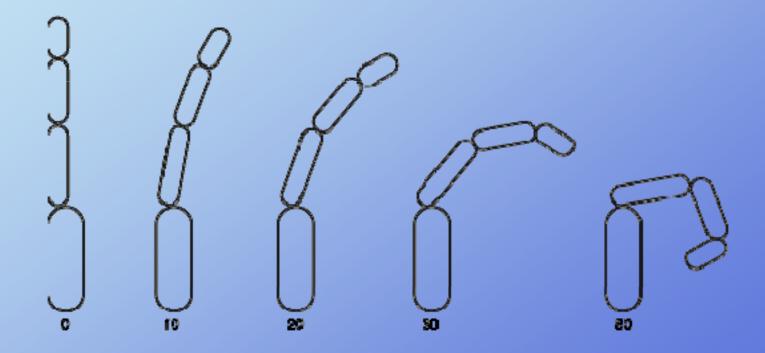
inma@aut.uah.es, manupg@aut.uah.es, ronan.boulic@epfl.ch, meziat@

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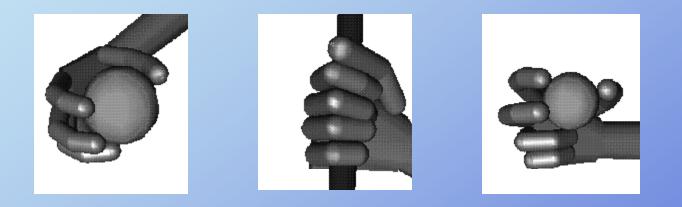
Modeling the Hand



Grasping

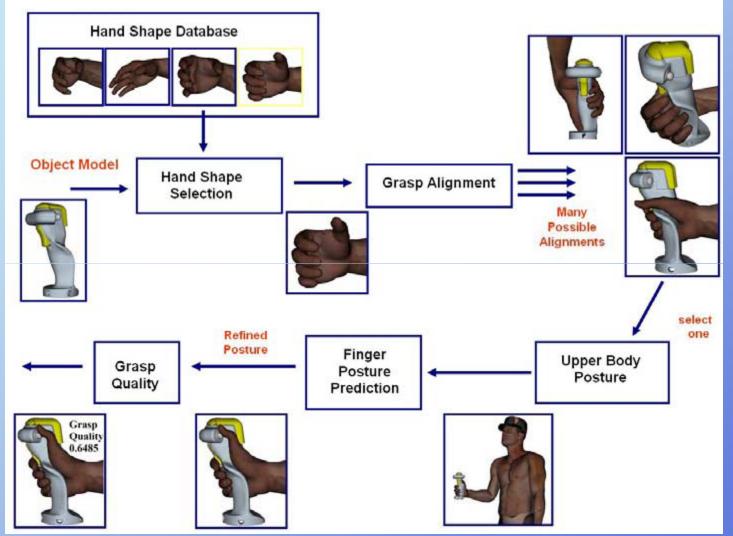


Grasping



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Graspina

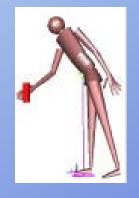


Grasp planning for digital humans Faisal Amer Goussous, U. of Iowa

Reaching - close v. distant

Extended grasping behavior for Autonomous Human Agents R. Max, R. Boulic, D. Thalmann







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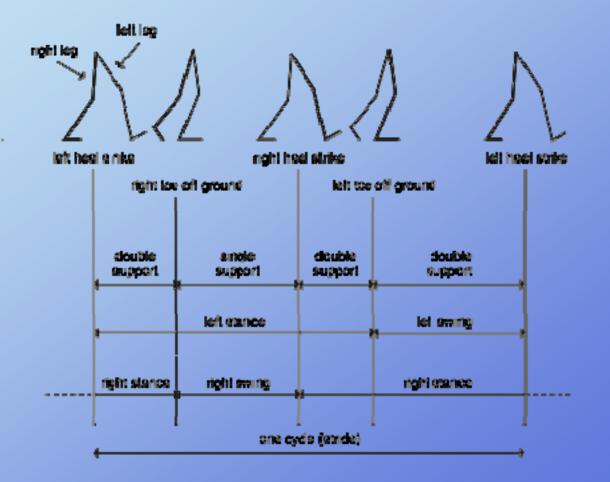
Mechanics of locomotion

walk cycle v. run cycle

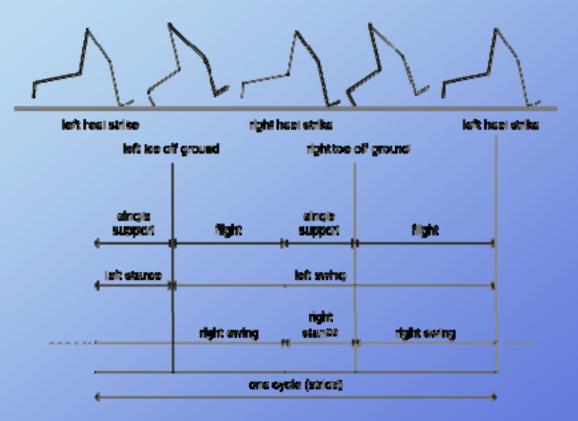
Pelvic transport Pelvic rotation Pelvic Tilt Knee flexion Ankle and toe joints

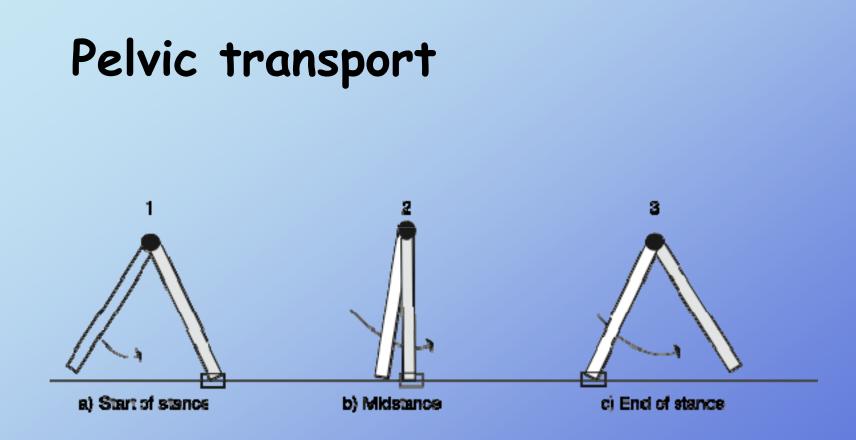
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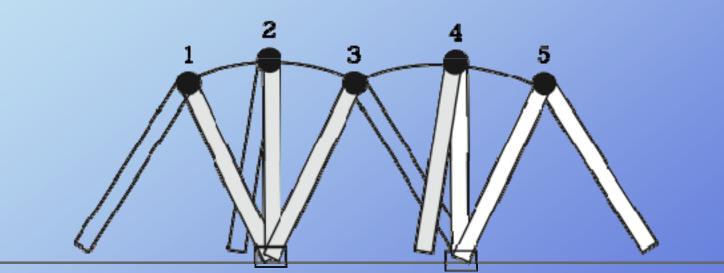






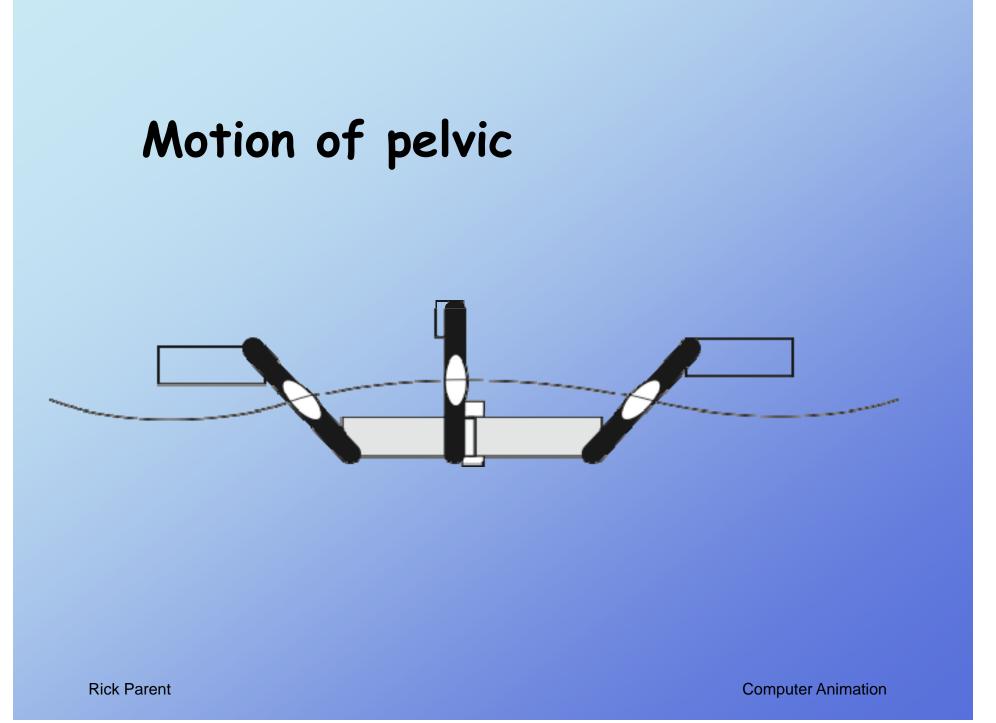


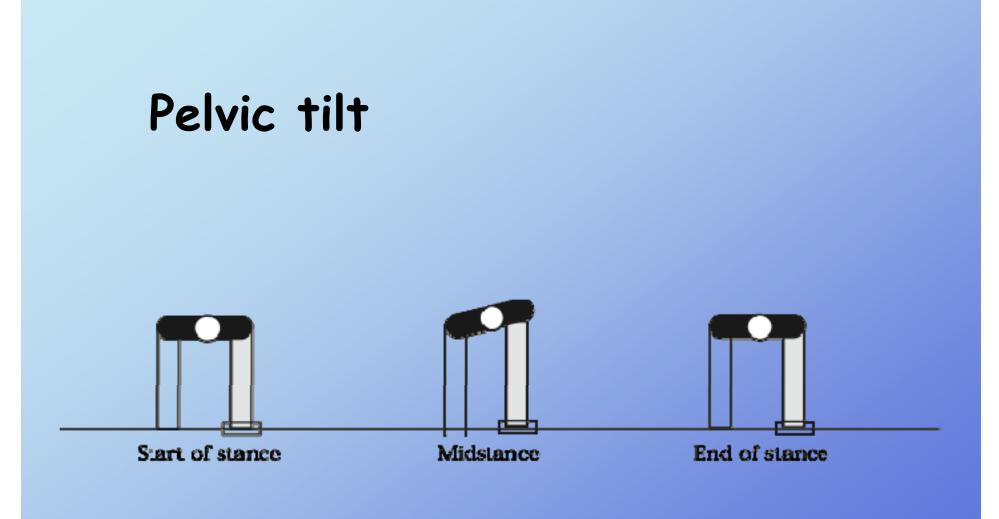


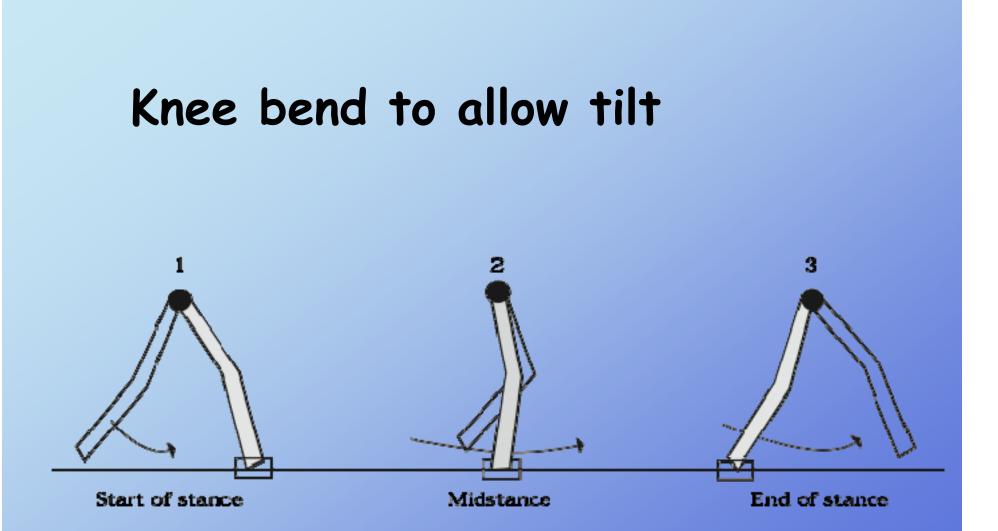


Pelvic rotation around hips

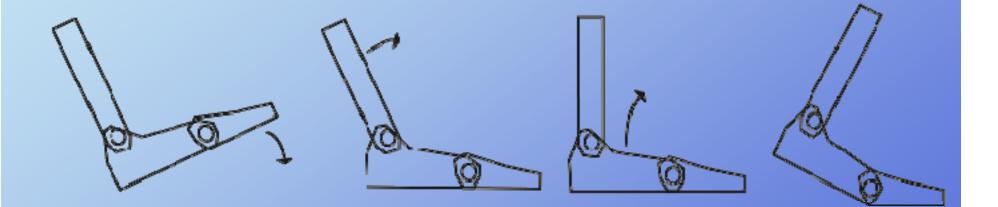




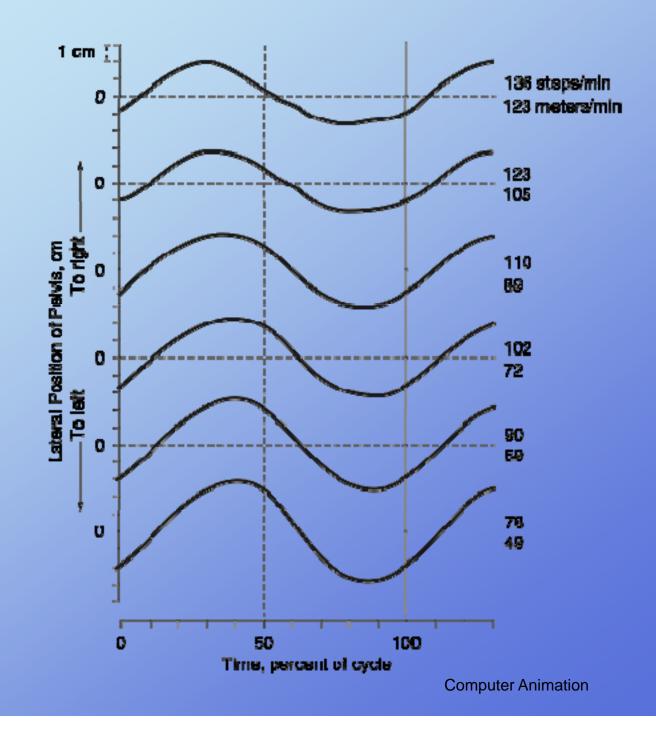




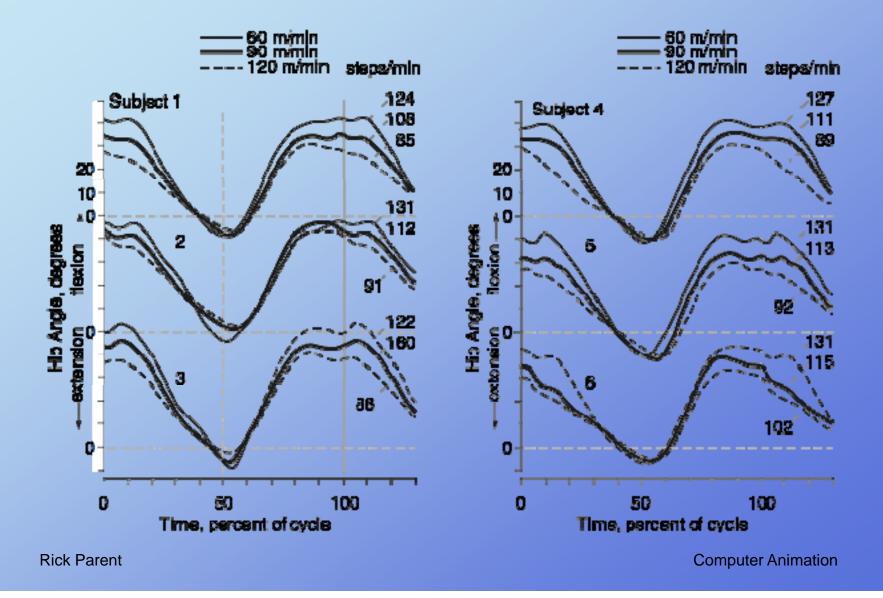
Ankle and Toe bend



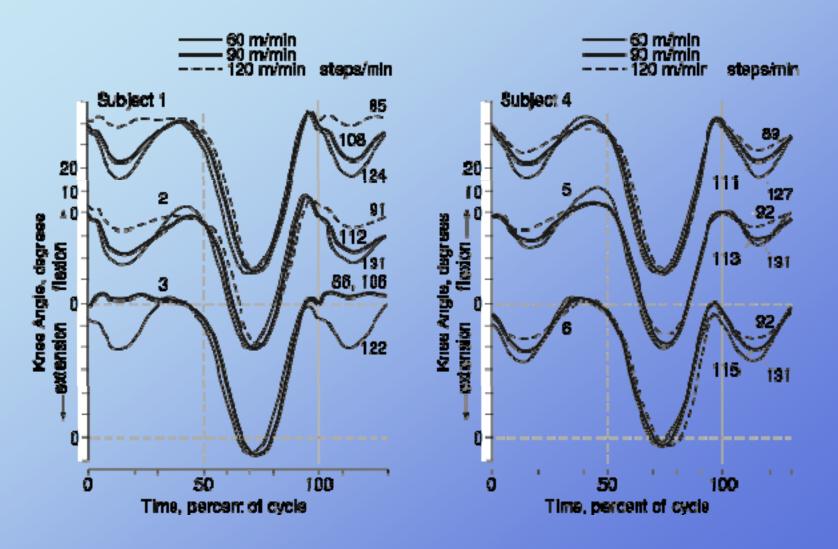




Walk Data

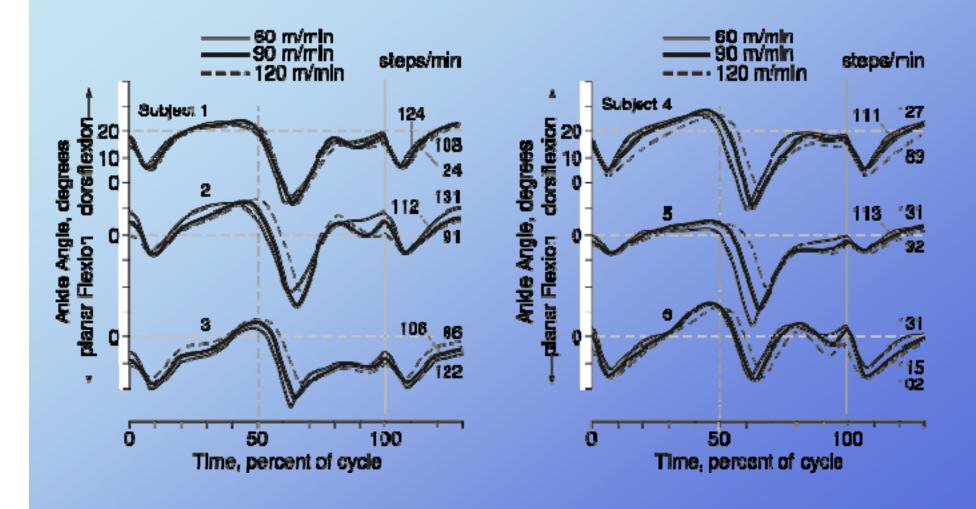


Walk Data



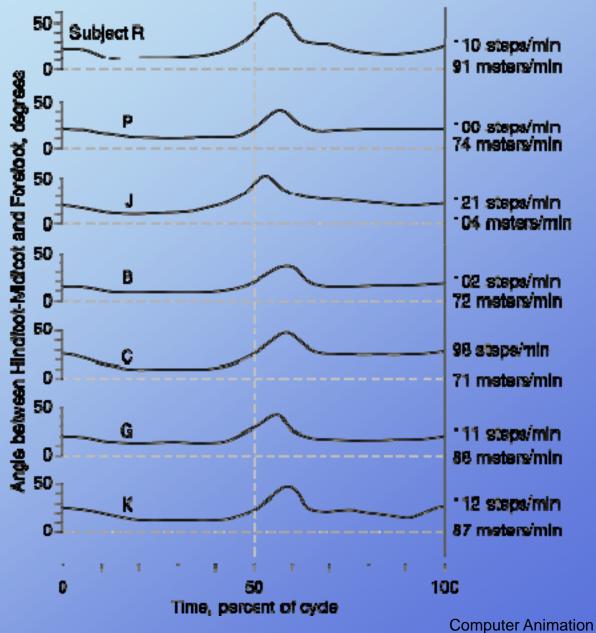
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Walk Data



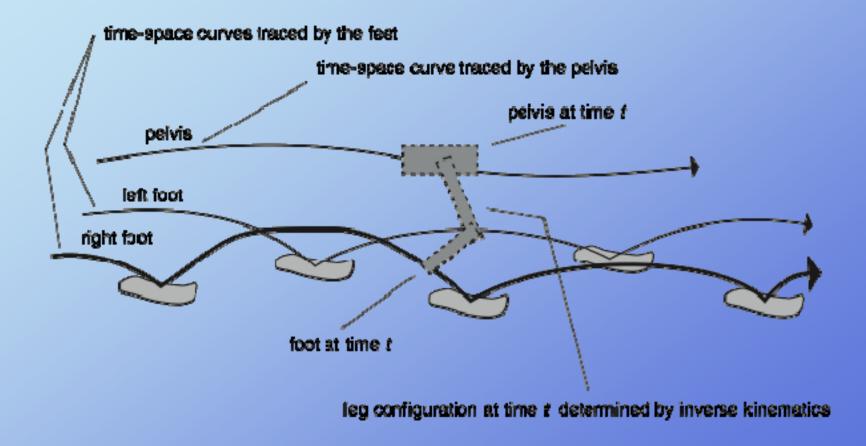
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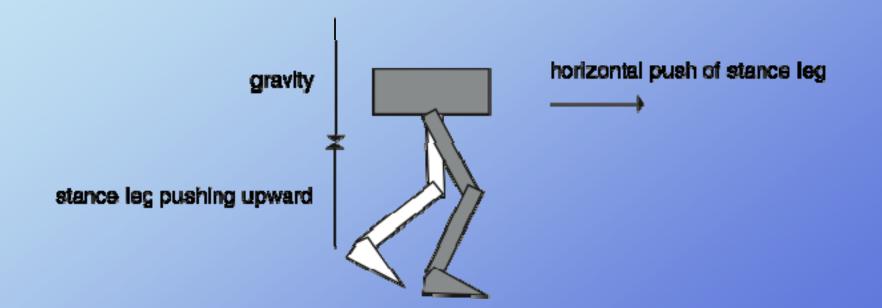


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Using Dynamics in the Walk



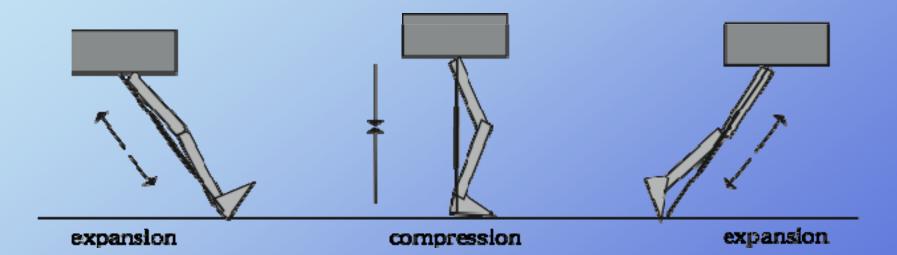
Using Dynamics in the Walk



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facial animation



Expressions v. speech

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facial animation

Parameterized facial attributues

Blend shapes

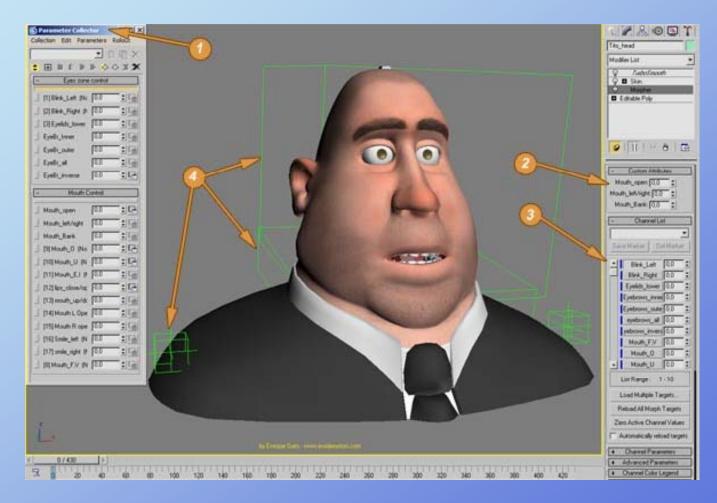
Muscle models surface muscles deep muscles

Performance (or data) driven instrumented (mocap system) video

http://www.youtube.com/watch?v=uQJ7gwG0G5g

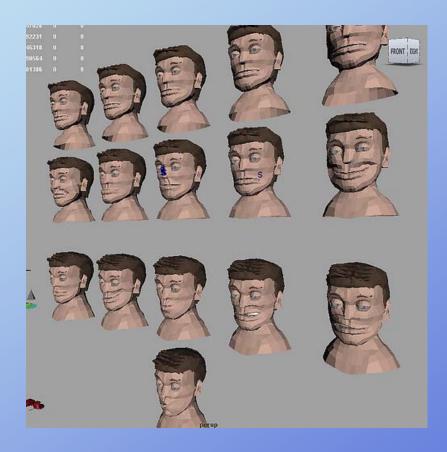
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Parameterized Facial features



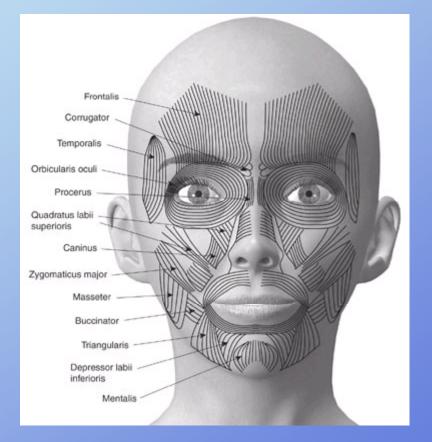
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Facial blend shapes



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Facial muscle model



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Surface muscle model

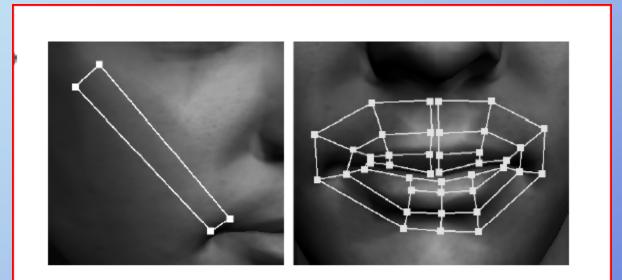


Figure 8: A simple grid (left, zygomatic major) and a non-uniform complex grid (right, orbicularis oris).

Geometry-based Muscle Modeling for Facial Animation Kolja K[°]ahler J[°]org Haber Hans-Peter Seidel

"computer animation" facial

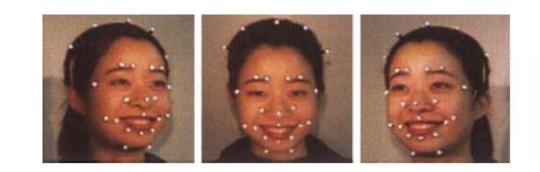


Figure 6. Snapshots taken simultaneously from three video cameras.

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"computer animation" facial

Text to speech Audio to speech Break down to phonemes

Phonemes to mouth shapes (visemes)

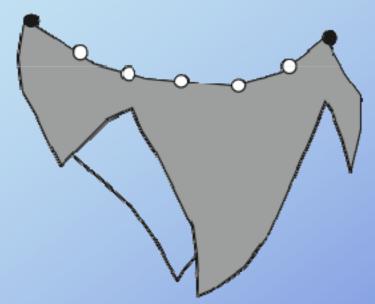
coarticulation

prosody

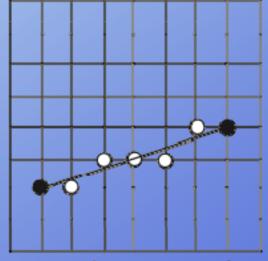
http://www.youtube.com/watch?v=fxADT-kZNrA

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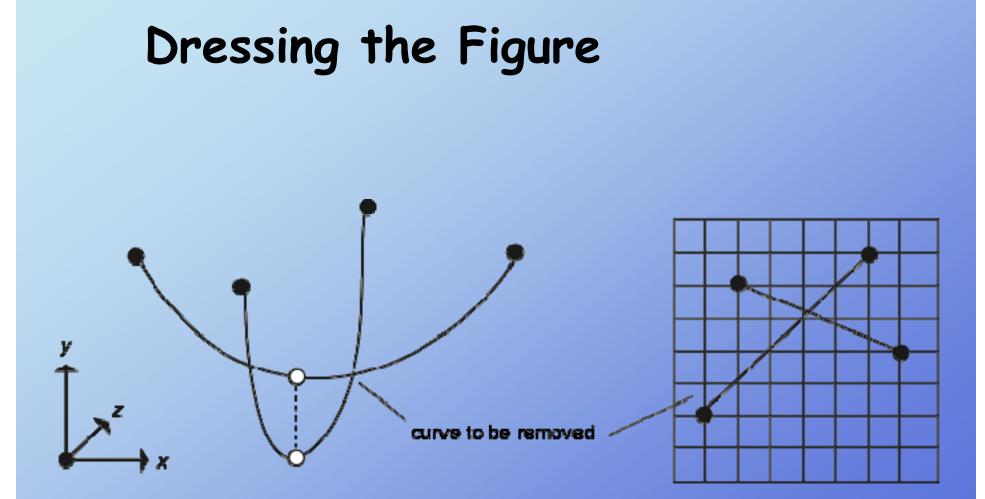
Cloth and clothing Simple draping Clothes Modeling dynamics Collision detection and response

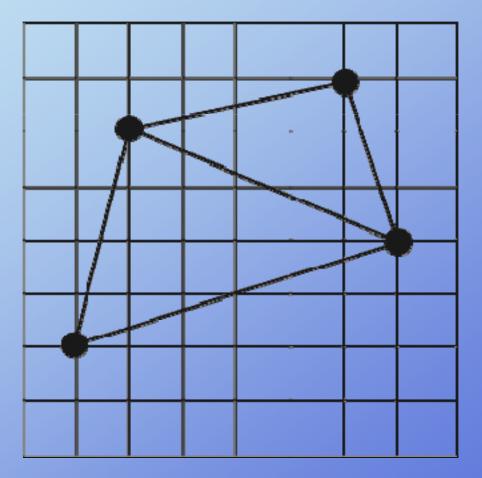


Cloth supported at two constrained points

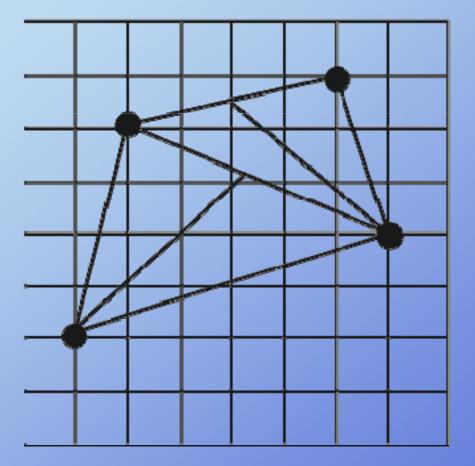


Constrained points in grid space

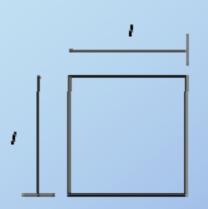




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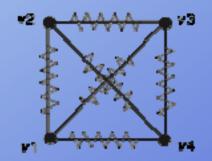
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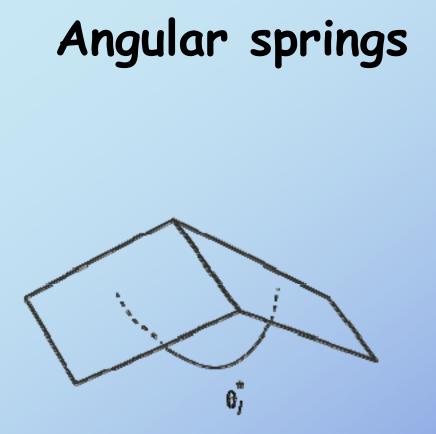
(a) Original quadrilateral of mesh



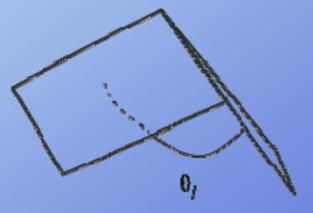
(b) Skew of original quadrilateral without changing the length of edges



(c) Diagonal springs to control skew

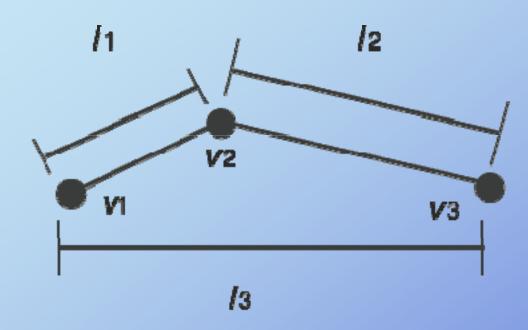


Original dihedral angle



Bending along the edge that changes dihedral angle

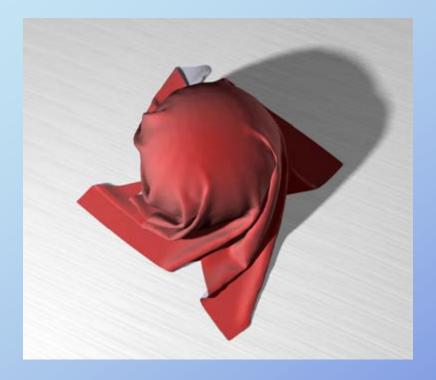
Angular springs



/1 = |V2 - V2|/2 = |V3 - V2|/3 = |V3 - V1|



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Complexity 100,000 strands

Collisions

Shadowing

Reflections

Hair types



Populate head with hair Design hairstyle Animate hair

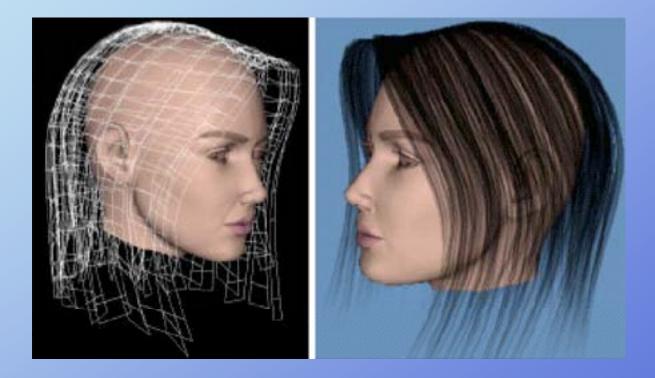


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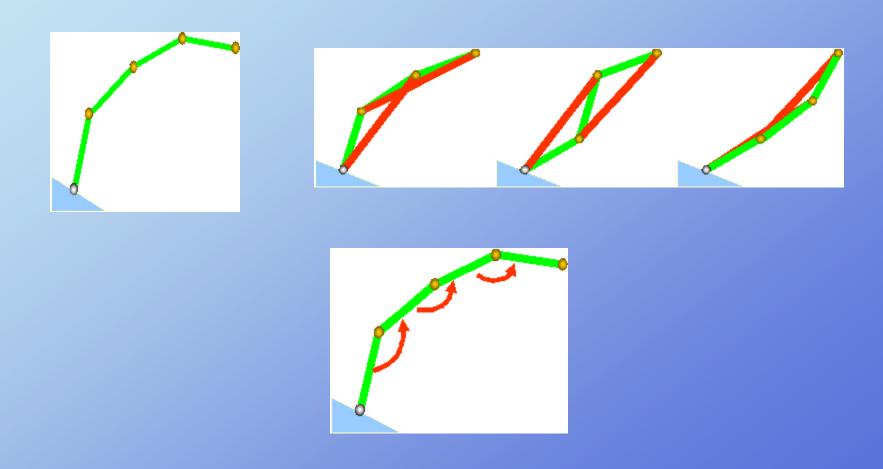


http://run.usc.edu/cs599-s10/hair/c33-hair-sig07.pdf

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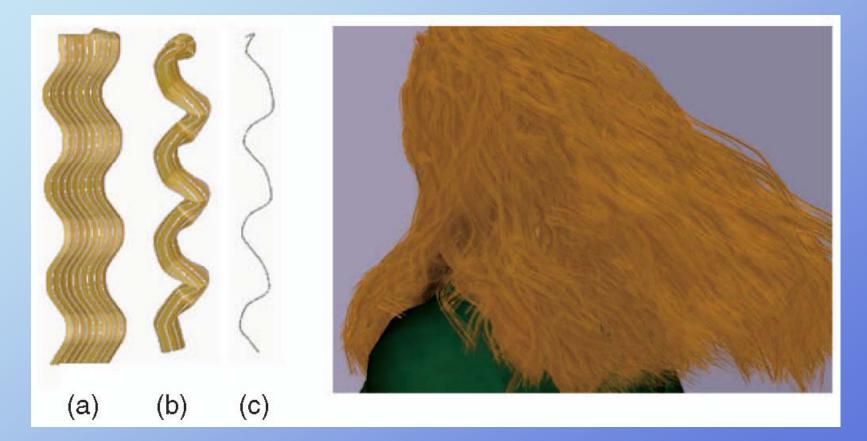






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Hair - Hierarchy



A Survey on Hair Modeling: Styling, Simulation, and Rendering Kelly Ward, Florence Bertails, Tae-Yong Kim, Stephen R. Marschner, Marie-Paule Cani, and Ming C. Lin,

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