

# The Shape Space of Discrete Orthogonal Geodesic Nets

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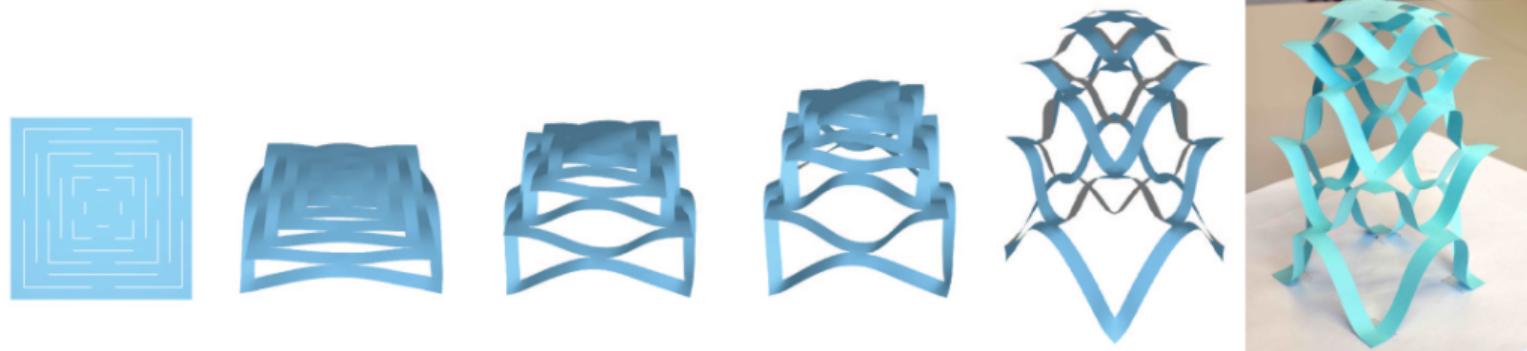
*Xianzhong Fang*

October 15, 2018

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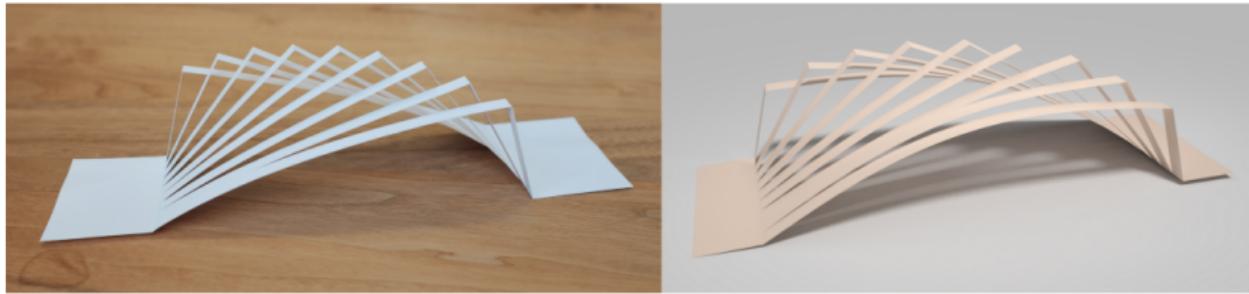
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# Developable surfaces



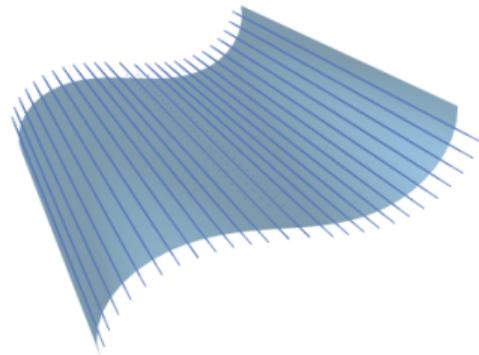
*Isometric deformation: no stretch and tear.*

# Developable surfaces

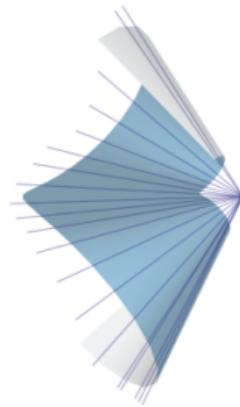


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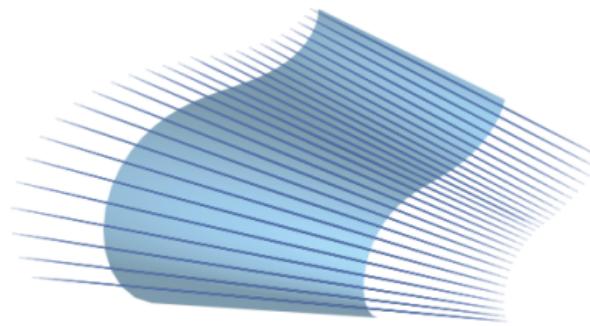
# Explicit Representation: Ruling



cylindrical surface

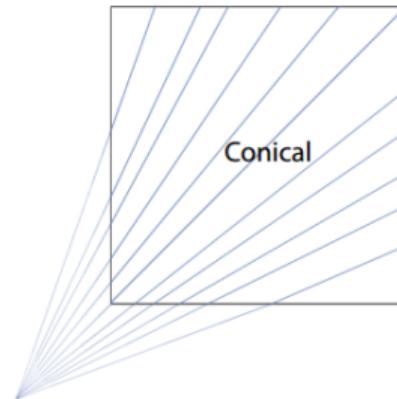
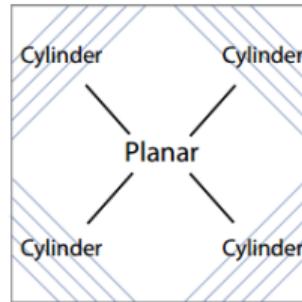


conical surface

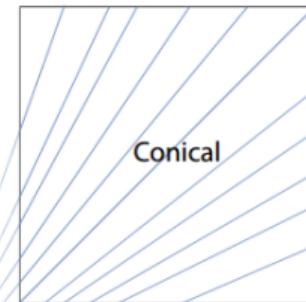
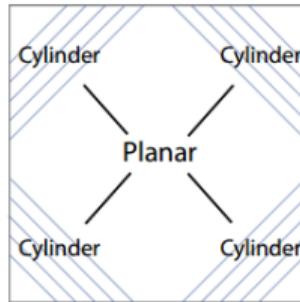


tangent surface

# Explicit Representation: Ruling

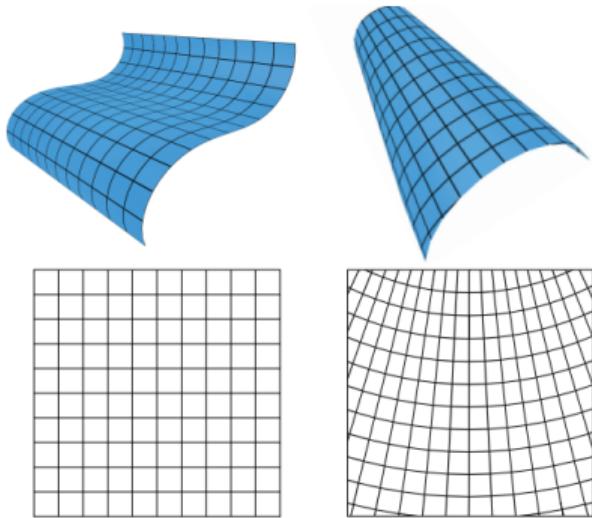


# Explicit Representation: Ruling

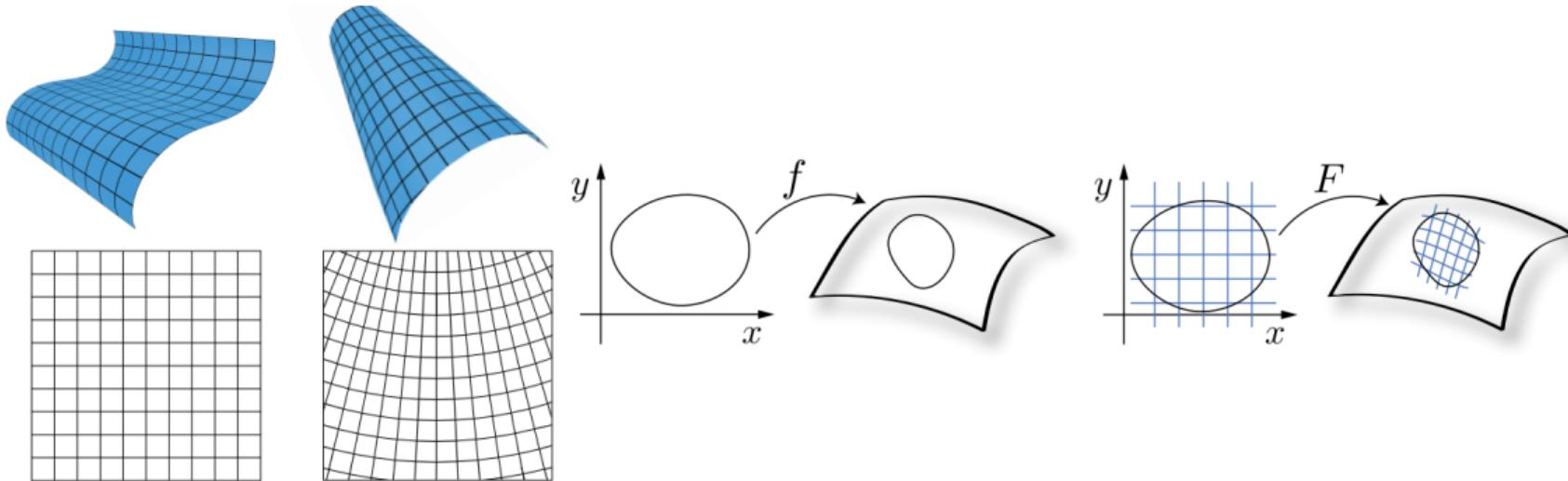


*Structure is very different: not easy for editing and modeling*

# Curvature Line Parameterization



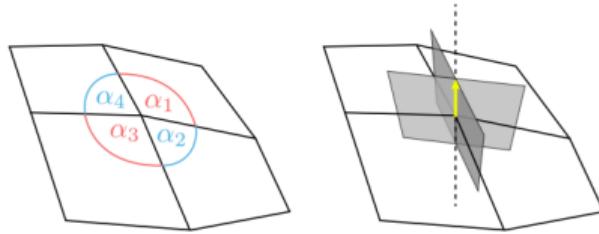
# Curvature Line Parameterization



# Discrete Orthogonal Geodesic Nets (DOG)

- **Corollary:** *A smooth surface is **developable** if and only if it can be locally parameterized by **orthogonal geodesics**.*

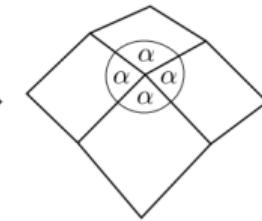
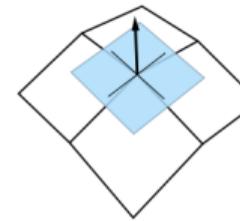
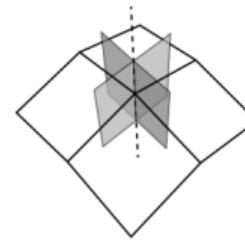
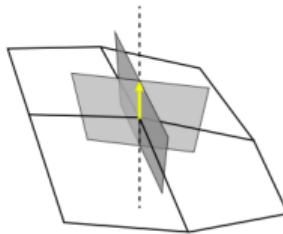
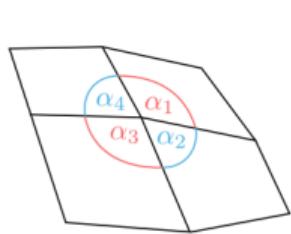
# Discrete Orthogonal Geodesic Nets (DOG)



*Geodesic: as straight as possible on surface*

$$\alpha_1 + \alpha_2 = \alpha_3 + \alpha_4, \alpha_1 + \alpha_4 = \alpha_2 + \alpha_3$$

# Discrete Orthogonal Geodesic Nets (DOG)



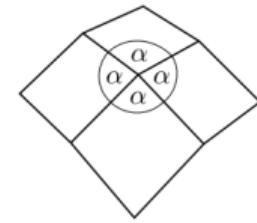
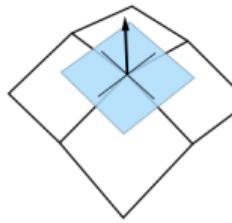
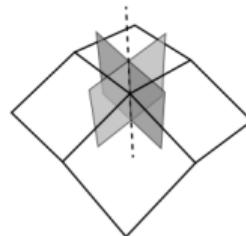
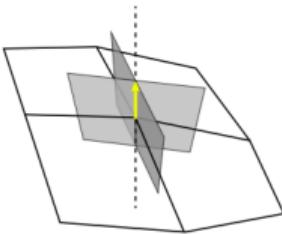
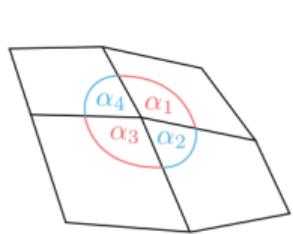
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*Orthogonal Geodesic*

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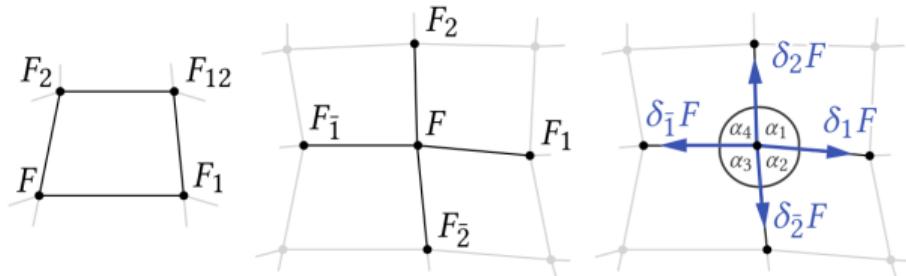


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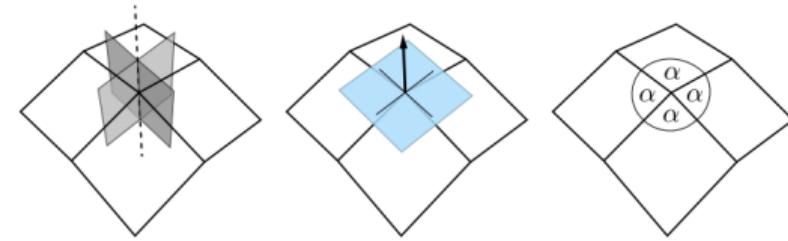
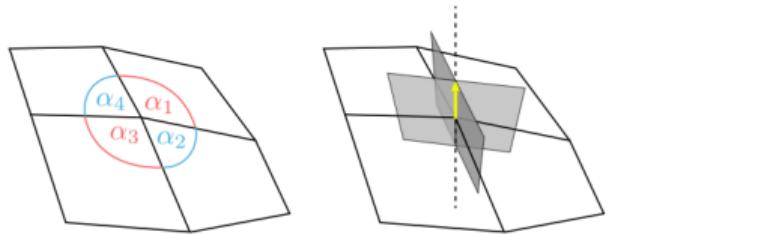
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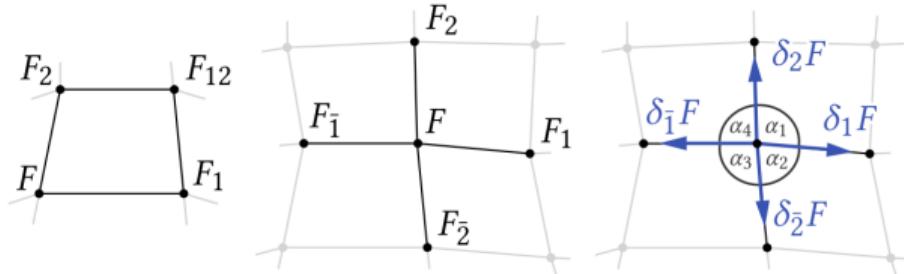


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$$\alpha_1 = \alpha_2 = \alpha_3 = \alpha_4$$



$$\phi_1(\mathbf{F}) := \cos(\alpha_1) - \cos(\alpha_2) = 0,$$

$$\phi_2(\mathbf{F}) := \cos(\alpha_2) - \cos(\alpha_3) = 0,$$

$$\phi_3(\mathbf{F}) := \cos(\alpha_3) - \cos(\alpha_4) = 0.$$

# Shape Space: DOG flow

- The Shape Space:  $\mathcal{M} = \{\mathbf{F} \in \mathcal{C} \mid \varphi_i(\mathbf{F}) = 0, \forall i = 1, 2, 3, \dots, m\}.$
- DOG Flow:  $\mathcal{F}(t) \in \mathcal{M}, \mathcal{F}(0) = F^0.$
- Tangent space of  $\mathcal{M}$  ( $T\mathcal{M}$ ):  $\frac{\partial \varphi}{\partial \mathbf{F}} = J_{F^0}, J_{F^0}x = 0.$

# Optimization

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- KKT system:

$$K \begin{pmatrix} \bar{\nabla}_M E(\mathbf{F}) \\ \lambda \end{pmatrix} = \mathbf{b}$$

$$K = \begin{pmatrix} M & J^T \\ J & 0 \end{pmatrix}, \quad \mathbf{b} = \begin{pmatrix} \nabla E(\mathbf{F}) \\ \mathbf{0} \end{pmatrix}$$

# Optimization

- Bending minimization:

$$E_H(\mathbf{F}) = \sum_{v_i \in \mathbf{F}} A_i H_i^2$$

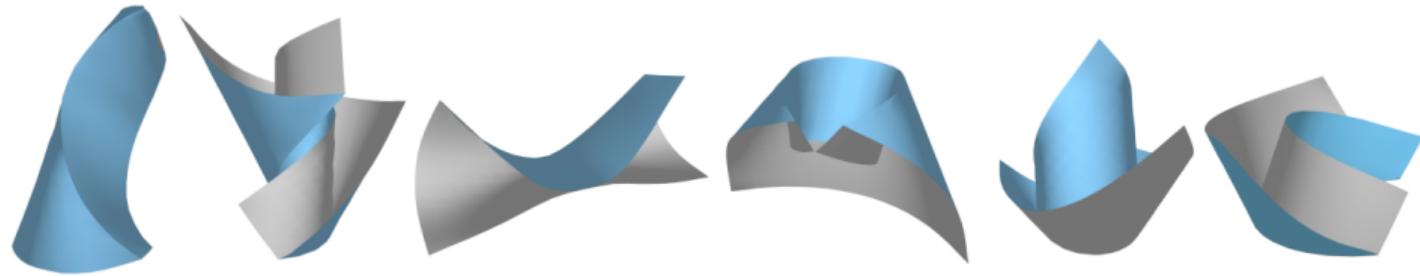
- Isometry term:

$$E_{iso}(\mathbf{F}) = \sum_{e \in \mathbf{F}} (\ell_e - \ell_e^0)^2$$

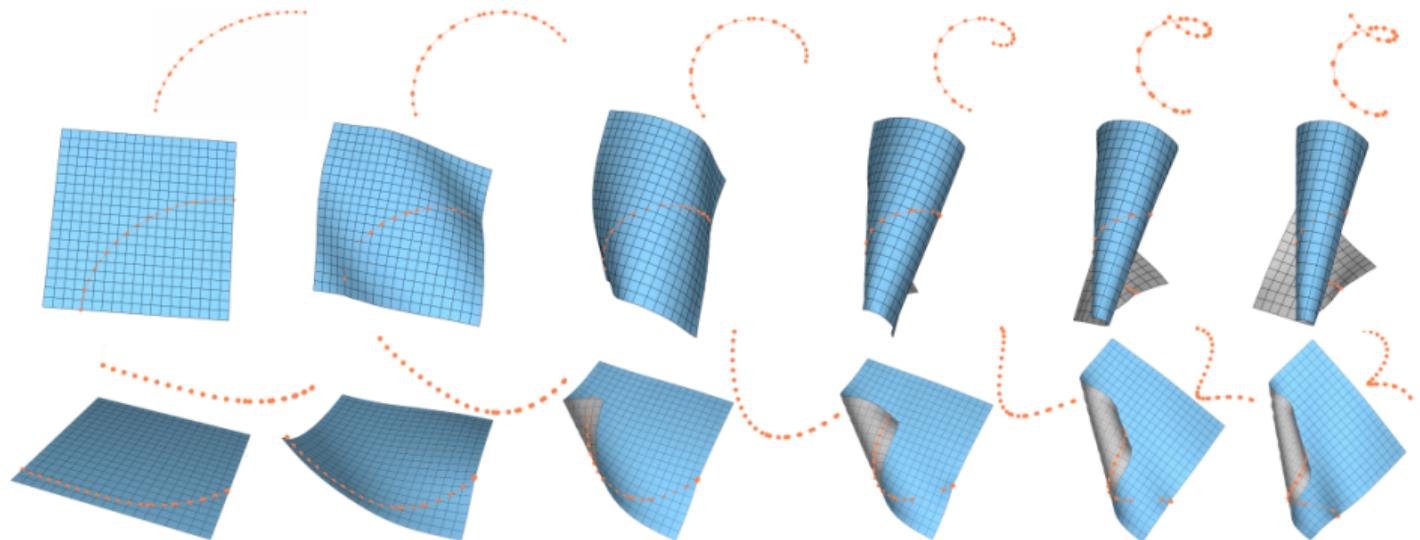
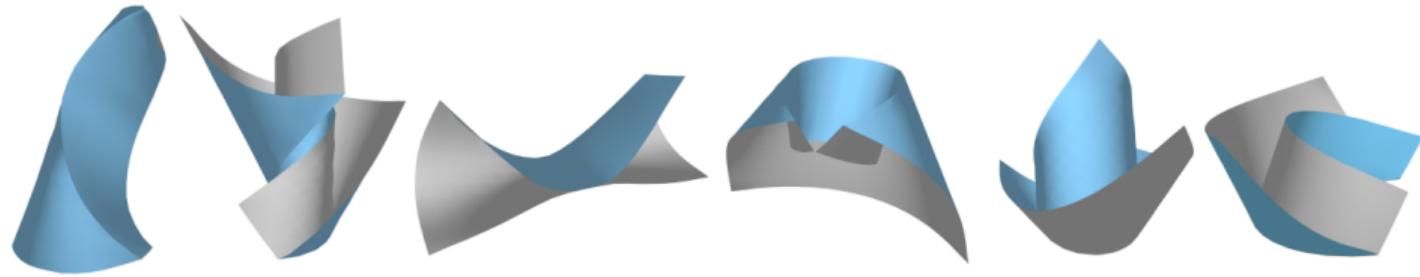
- Positional constraints:

$$\sum_{i \in C} \|F(i) - C(i)\|^2$$

# Results



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# Limitations

- Timecost is high: restricted to rather coarse models for interactive editing.
- No support for intricate crease patterns: here each crease curve is simple and starts and ends at a mesh boundary.

# Thanks!