

# IFT 6113

## SURFACE RECONSTRUCTION

[tiny.cc/ift6113](http://tiny.cc/ift6113)

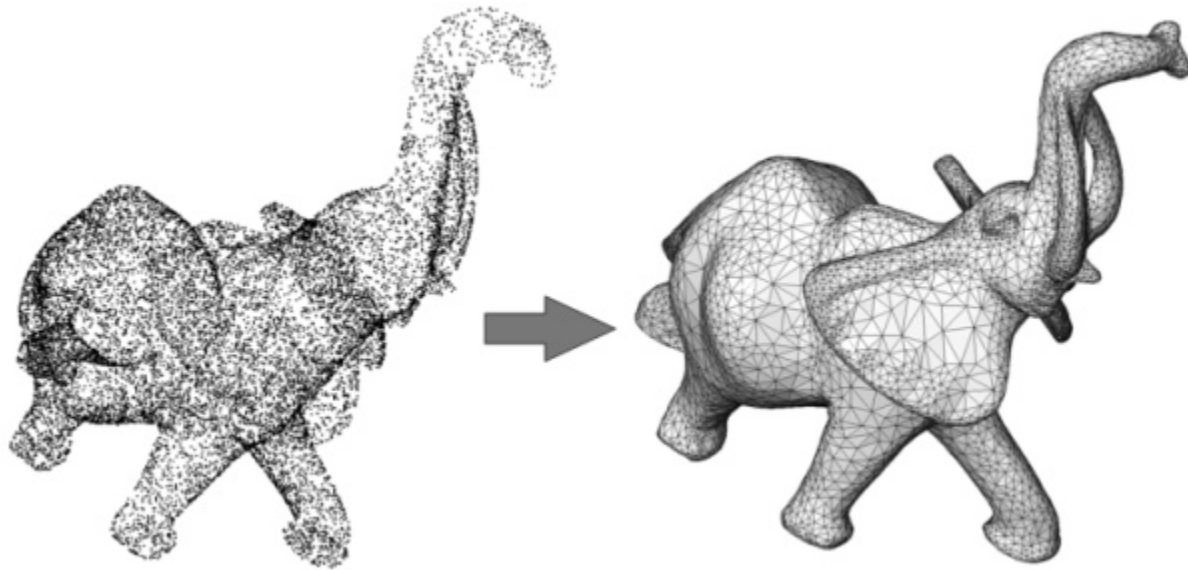
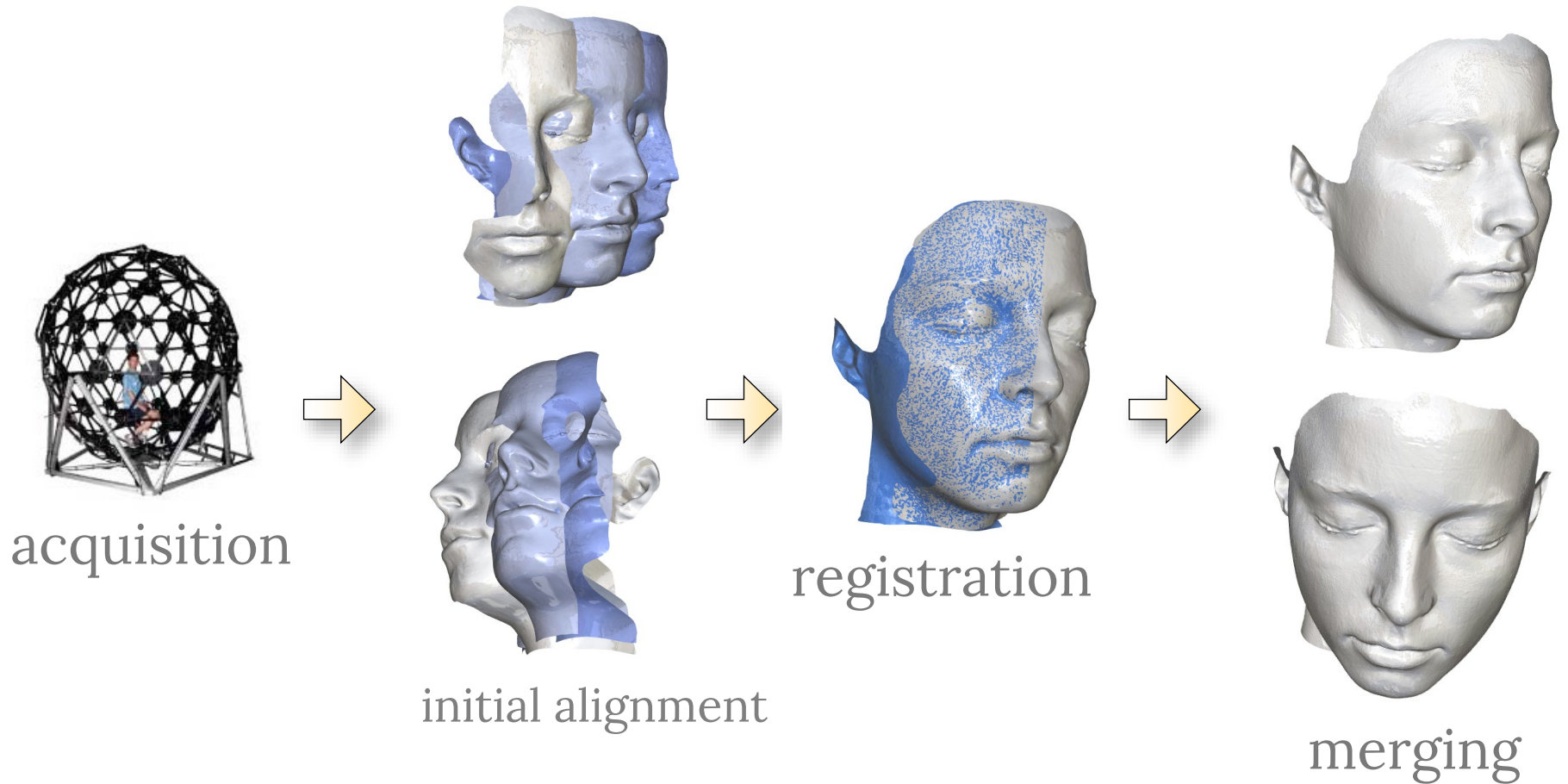


Image from [https://doc.cgal.org/latest/Poisson\\_surface\\_reconstruction\\_3/index.html](https://doc.cgal.org/latest/Poisson_surface_reconstruction_3/index.html)

# Mikhail Bessmeltsev

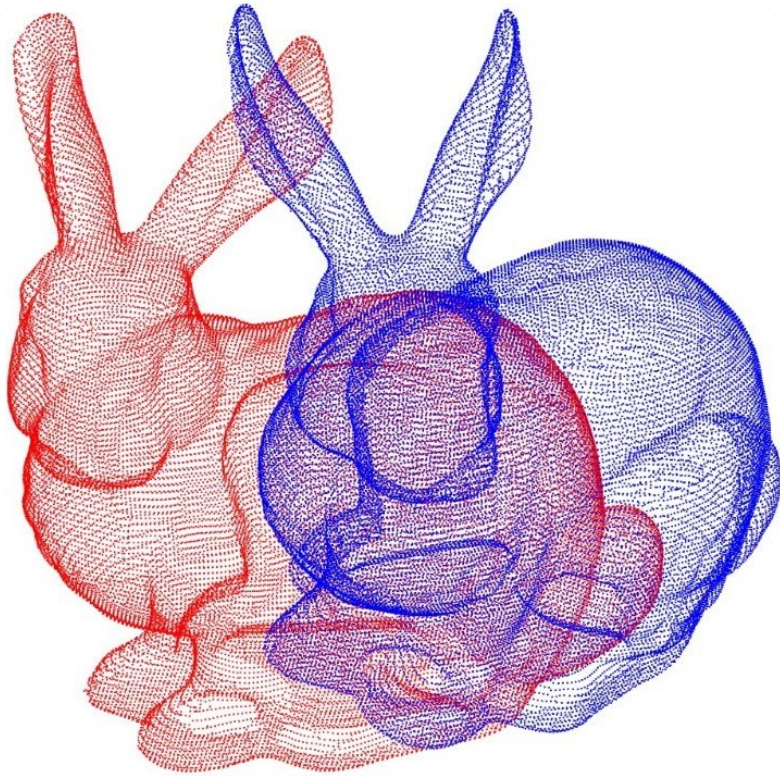
Some slides from Justin Solomon, Alla Sheffer, and Hao Li

# 3D Reconstruction Pipeline



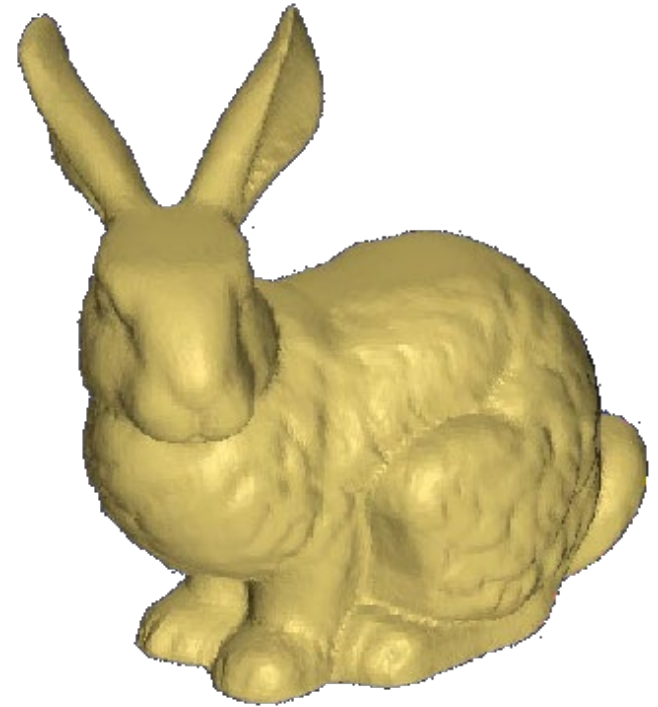
*Data provided by Paramount Pictures and Aguru Images*

# Two components



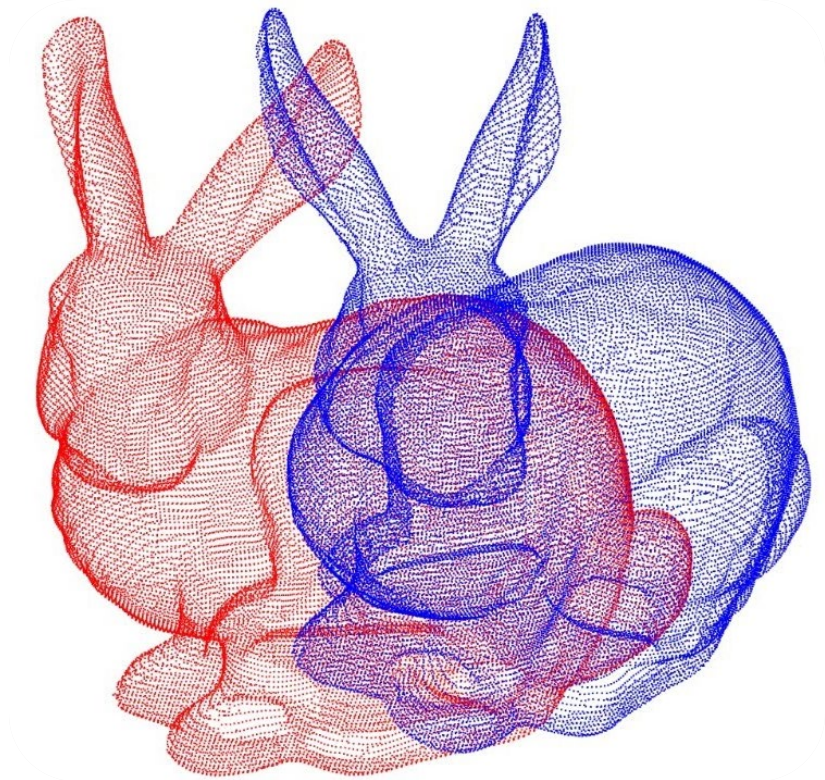
[https://i.ytimg.com/vi/uzOCS\\_gdZuM/maxresdefault.jpg](https://i.ytimg.com/vi/uzOCS_gdZuM/maxresdefault.jpg)

## Registration



## Meshing

# Two components



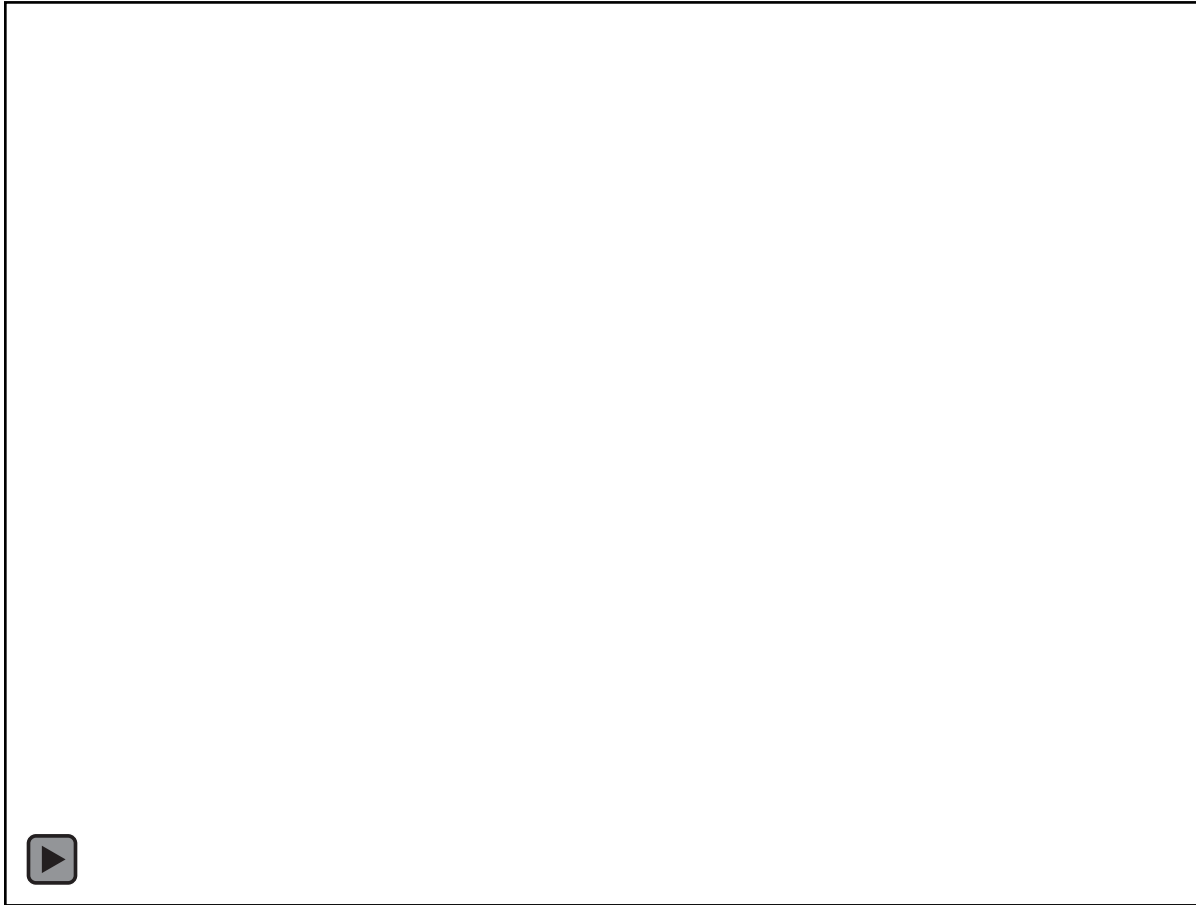
[https://i.ytimg.com/vi/uzOCS\\_gdZuM/maxresdefault.jpg](https://i.ytimg.com/vi/uzOCS_gdZuM/maxresdefault.jpg)

Registration



Meshing

# Registration Problem

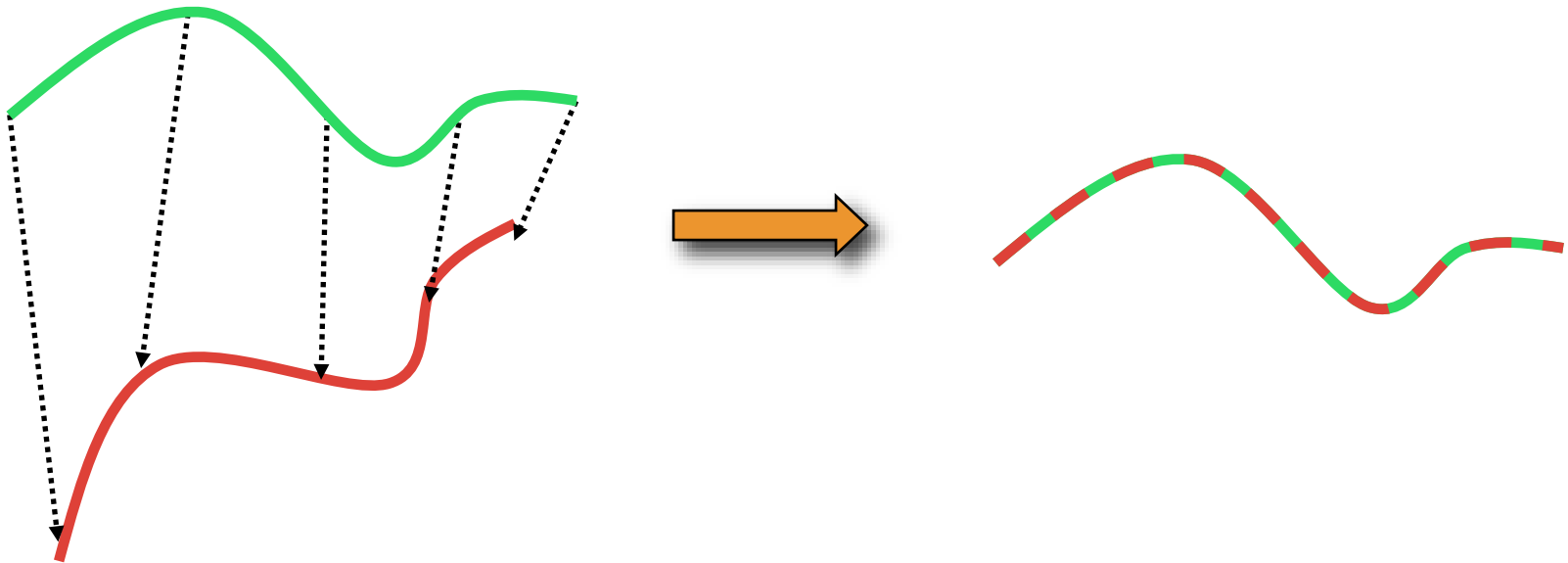


**Align two overlapping objects**

# Rough Plan

- **ICP algorithm**  
*A classic!*
- **ICP variants**

# Starting Point



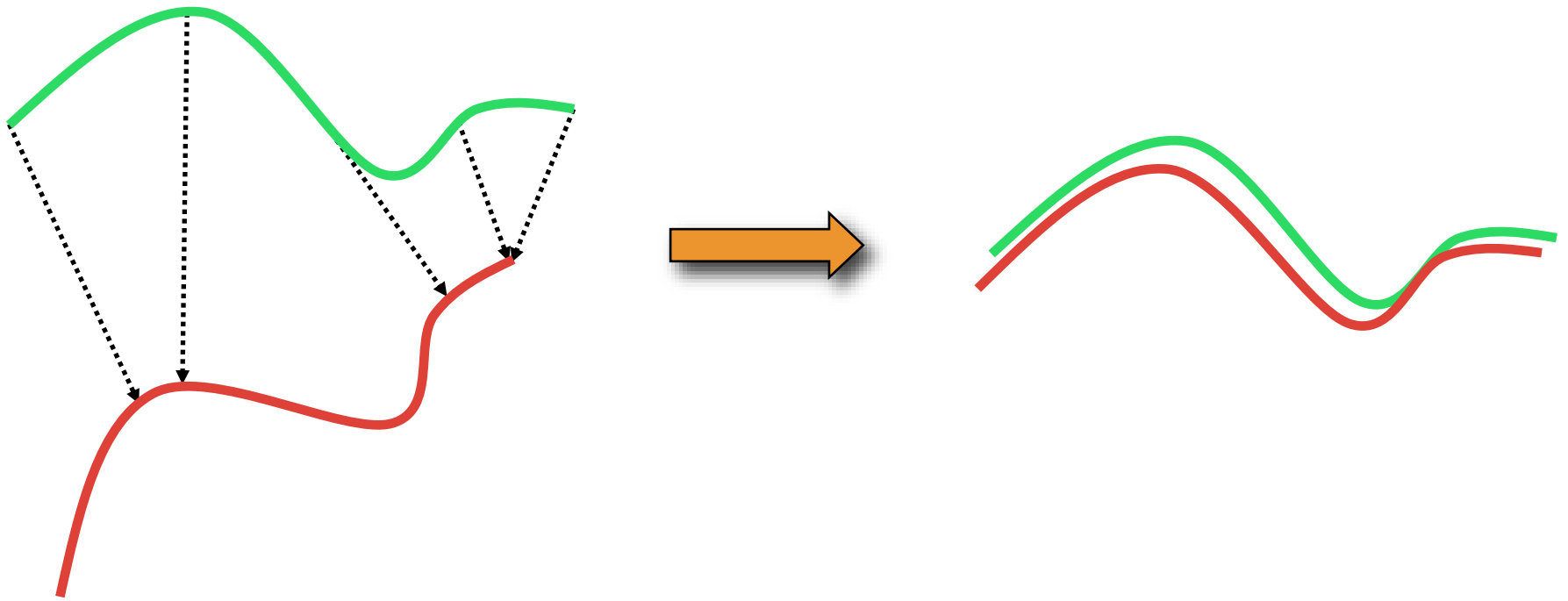
$$q_i = Rp_i + t$$

Can align given enough matches

**How many  
correspondences  
determine  $R$  and  $t$ ?**

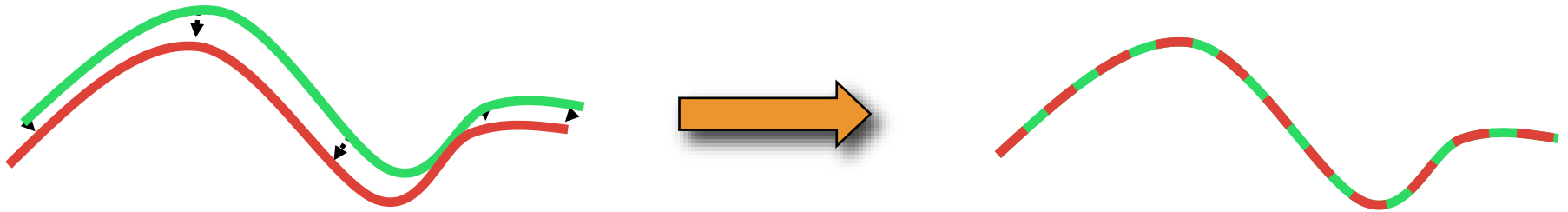
**How do you get  
correspondences?**

# Rough Approximation



**Closest points correspond**

# Try a Second Time...



# Iterative Closest Point (ICP)

- **Choose** e.g. 1000 random points
- **Match** each to closest point on other scan

- **Reject** pairs with distance  $> k$  times median

- **Minimize** 
$$E[R, t] := \sum_i \|Rp_i + t - q_i\|^2$$

- **Iterate** “A method for registration of 3-D shapes.”  
Besl and McKay, PAMI 1992.

# On the Board

$$\min_{t \in \mathbb{R}^3, R^\top R = I} \sum_i \|Rp_i + t - q_i\|^2$$

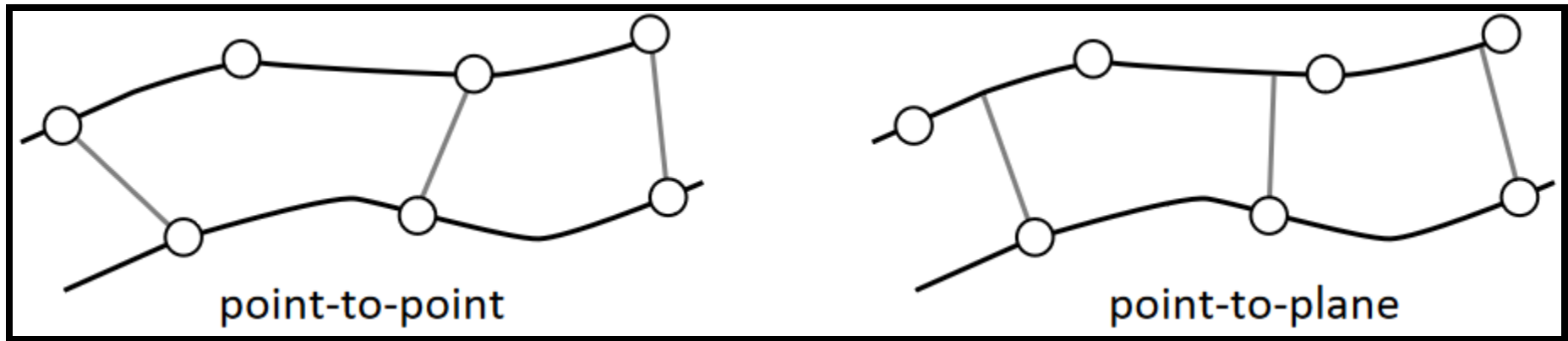
**Closed-form formulas!**

# Many (!) Variants of ICP

- **Source points** from one or both meshes
- **Matching** to points in the other mesh
  - **Weighting** correspondences
  - Rejecting **outlier** point pairs
  - Alternative **error metrics**

# Point-to-Plane Error Metric

Flat parts can slide along each other



$$E[R, t] := \sum_i ((Rp_i + t - q_i)^\top n_i)^2$$

$$\approx \sum_i [(p_i - q_i)^\top n_i + r^\top (p_i \times n_i) + t^\top n_i]^2 \text{ after linearizing}$$

where  $r := (r_x, r_y, r_z)$

**Least-squares!**

“Object modelling by registration of multiple range images”

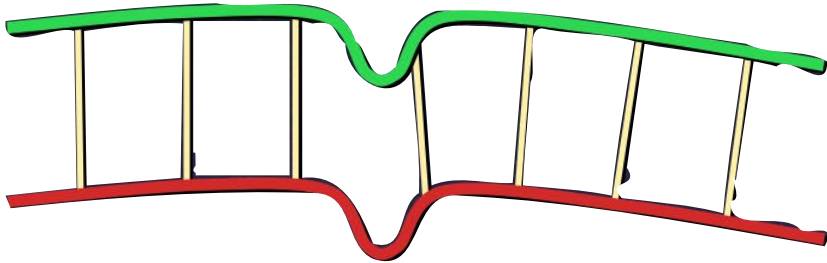
Chen and Medioni, Image and Vision Computing 10.3 (1992); image courtesy N. Mitra

# Closest Compatible Point

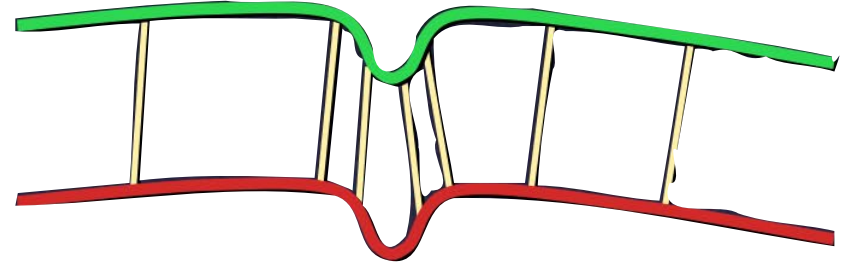
**Can improve matching effectiveness by restricting match to **compatible** points**

- Compatibility of colors [Godin et al. 94]
- Compatibility of normals [Pulli 99]
- Other possibilities:  
curvatures, higher-order derivatives, and other local features

# Choose Points to Improve Stability



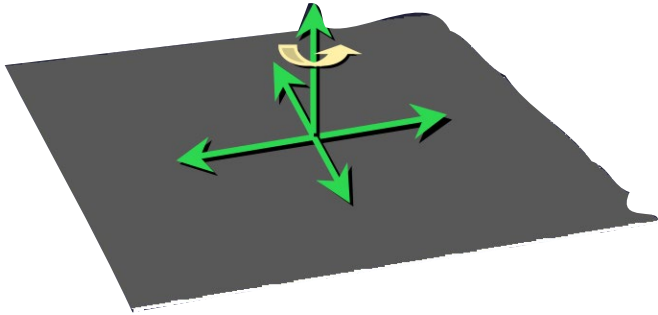
Uniform Sampling



Stable Sampling

**Sample discriminative points**

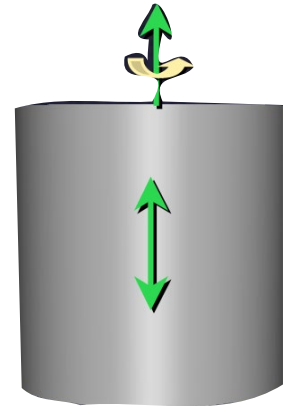
# Local Covariance



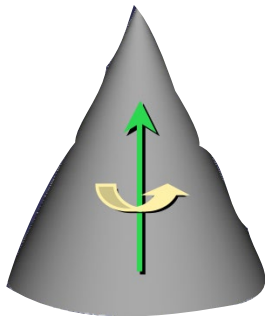
**3 small eigenvalues**  
2 translation  
1 rotation



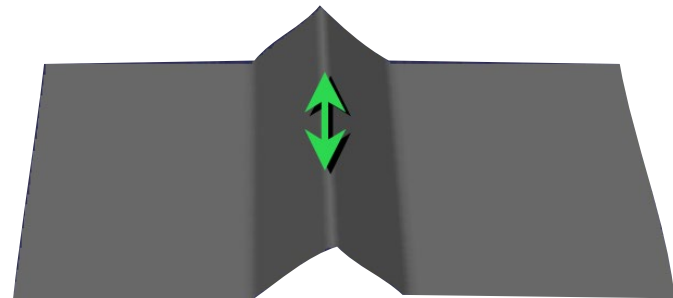
**3 small eigenvalues**  
3 rotation



**2 small eigenvalues**  
1 translation  
1 rotation



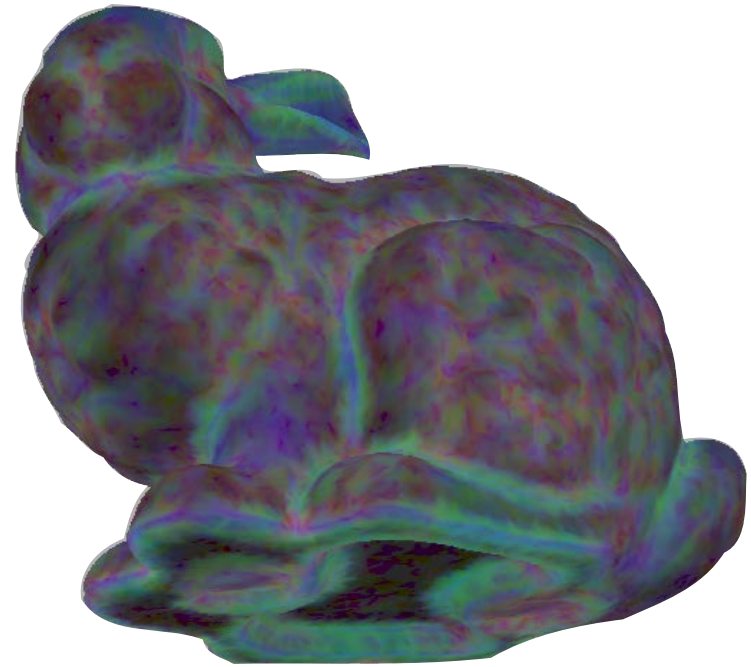
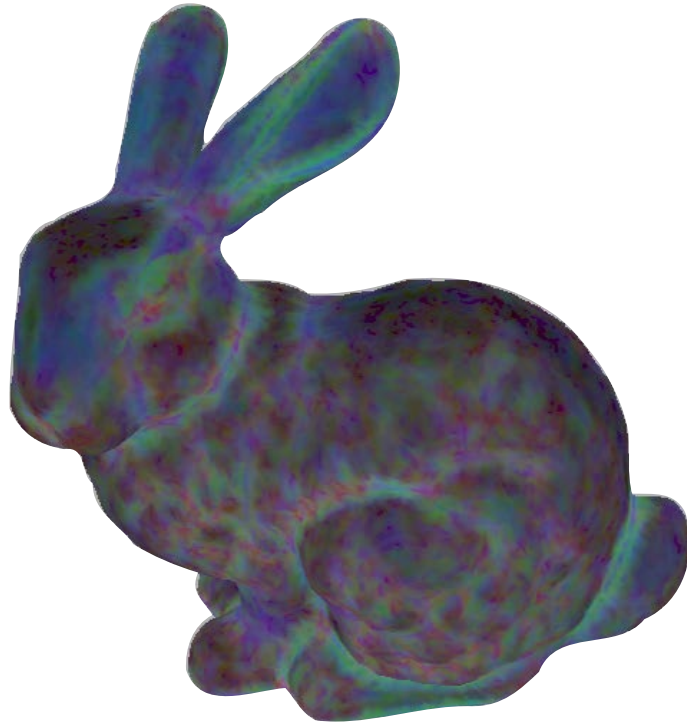
**1 small eigenvalue**  
1 rotation



**1 small eigenvalue**  
1 translation

[Gelfand et al. 2004]

# Stability Analysis



**Key:**



3 DOFs stable



5 DOFs stable

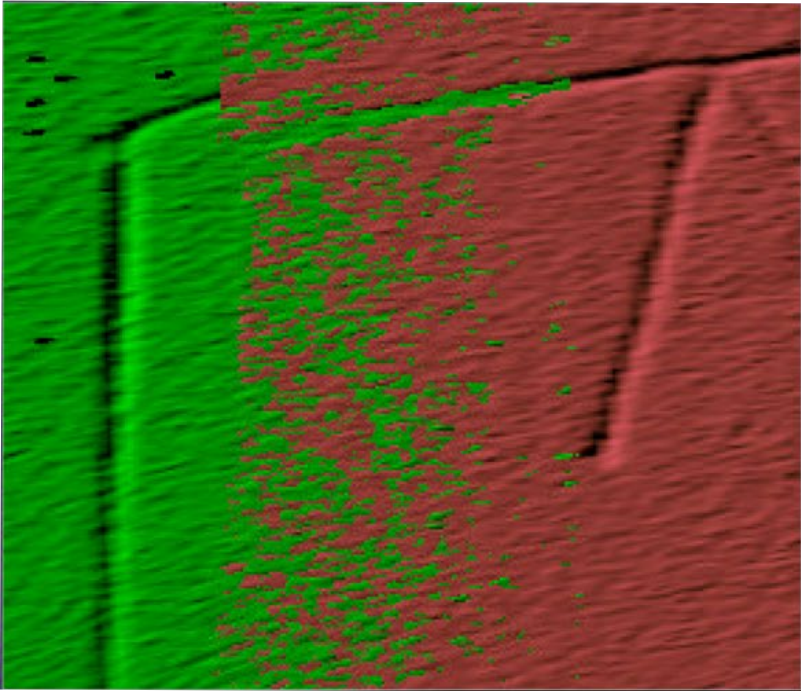


4 DOFs stable

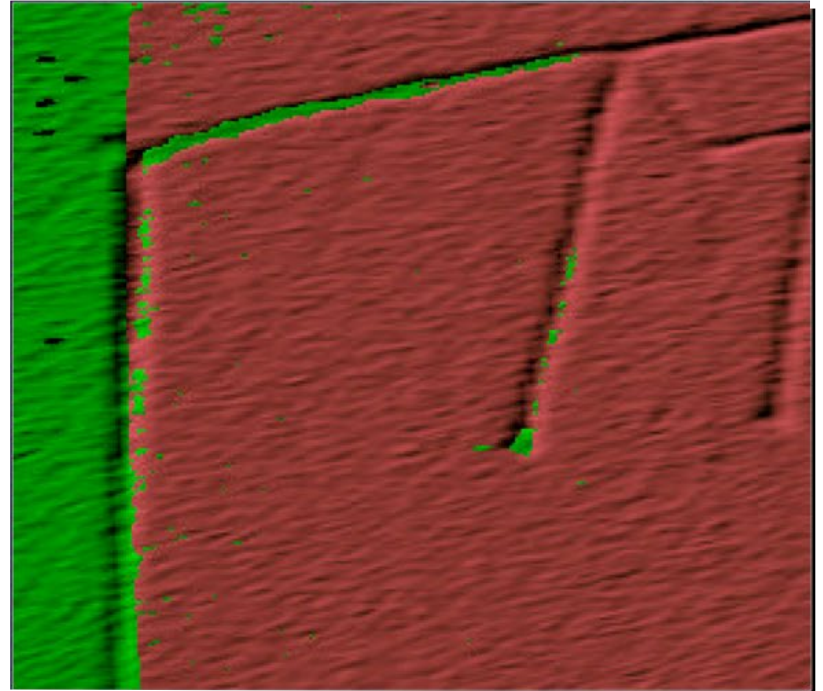


6 DOFs stable

# Alternative: Uniform Normals

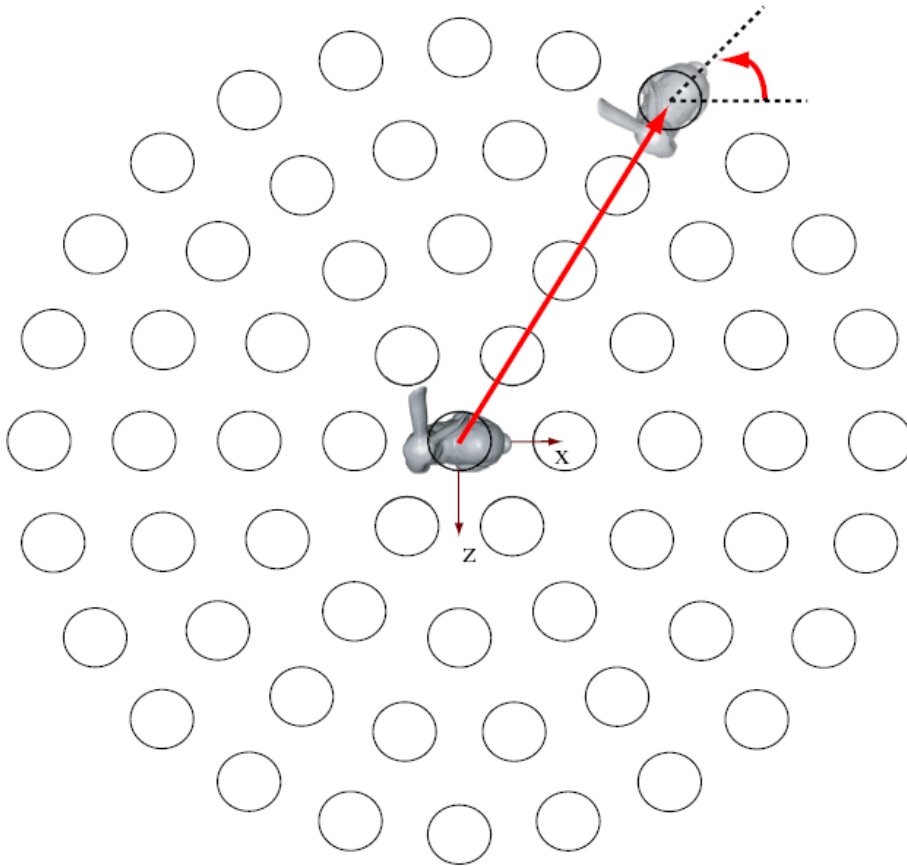


Random Sampling

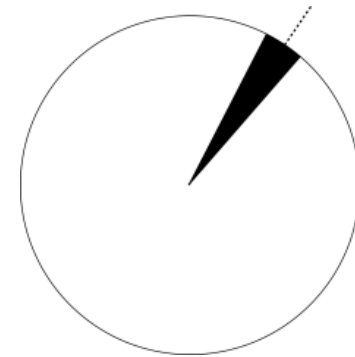


Normal-space Sampling

# Convergence Funnel Visualization

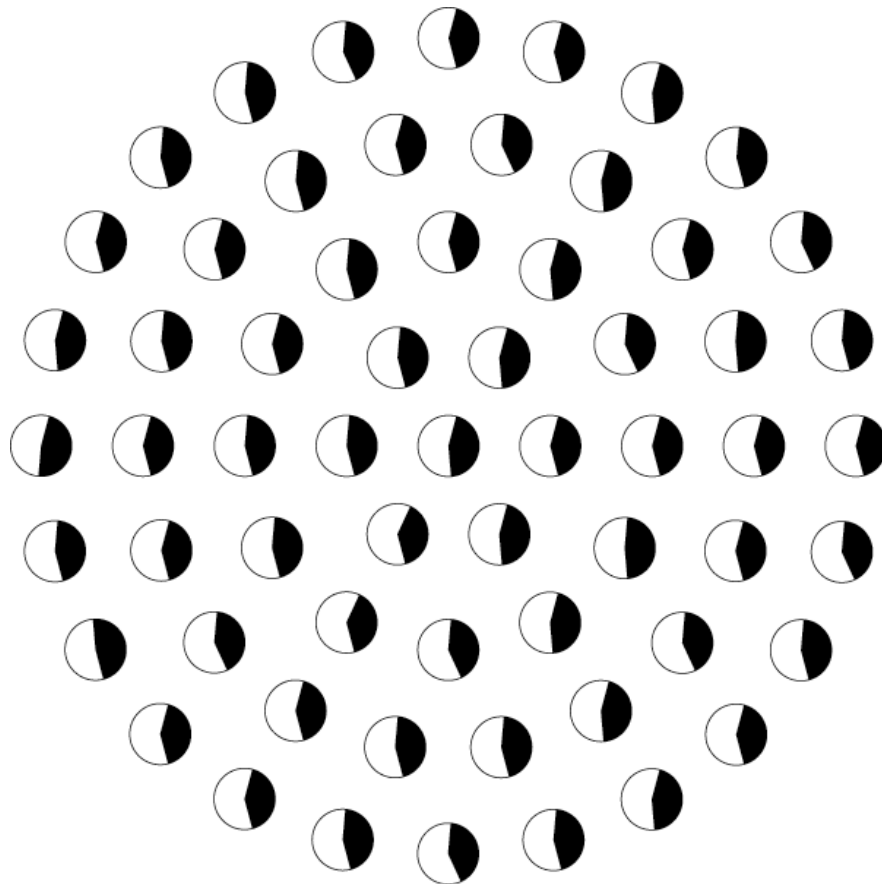


**Translation** in xz plane  
**Rotation** about y

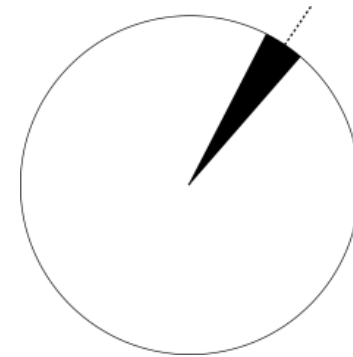


- Converges
- Does not converge

# Distance Field Method



**Translation** in  $xz$  plane  
**Rotation** about  $y$

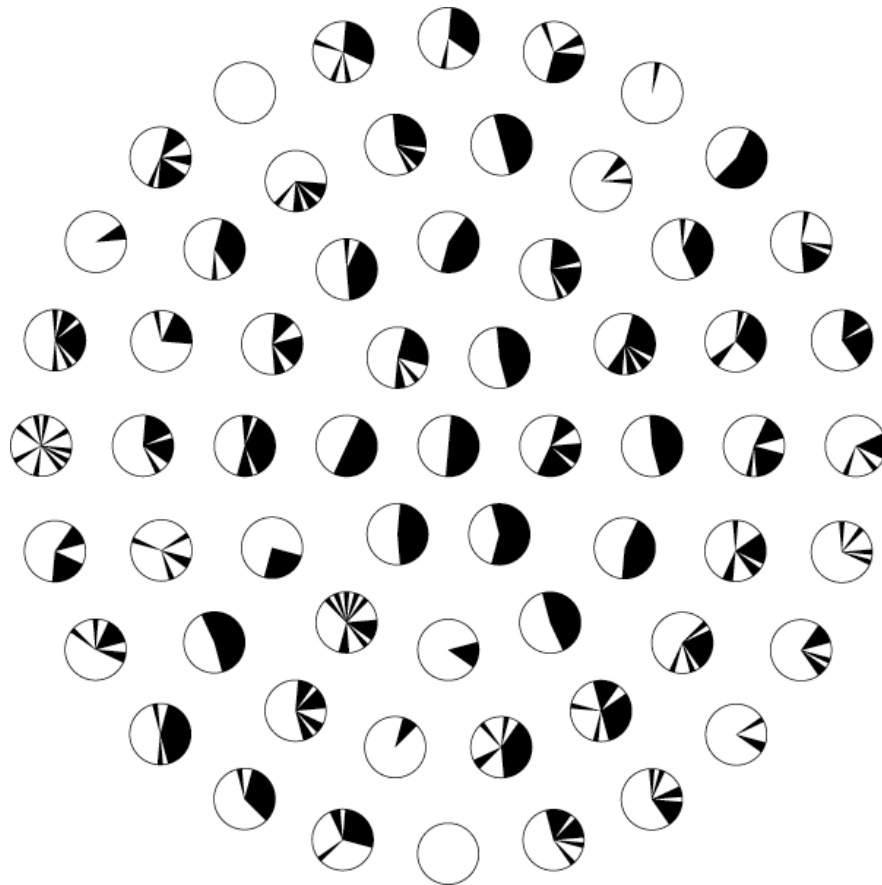


Converges

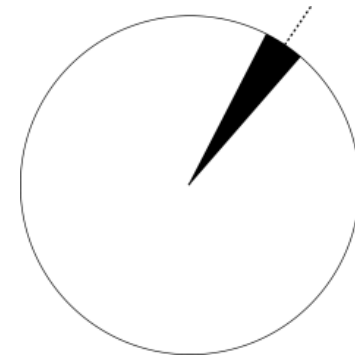


Does not converge

# Point-to-Plane

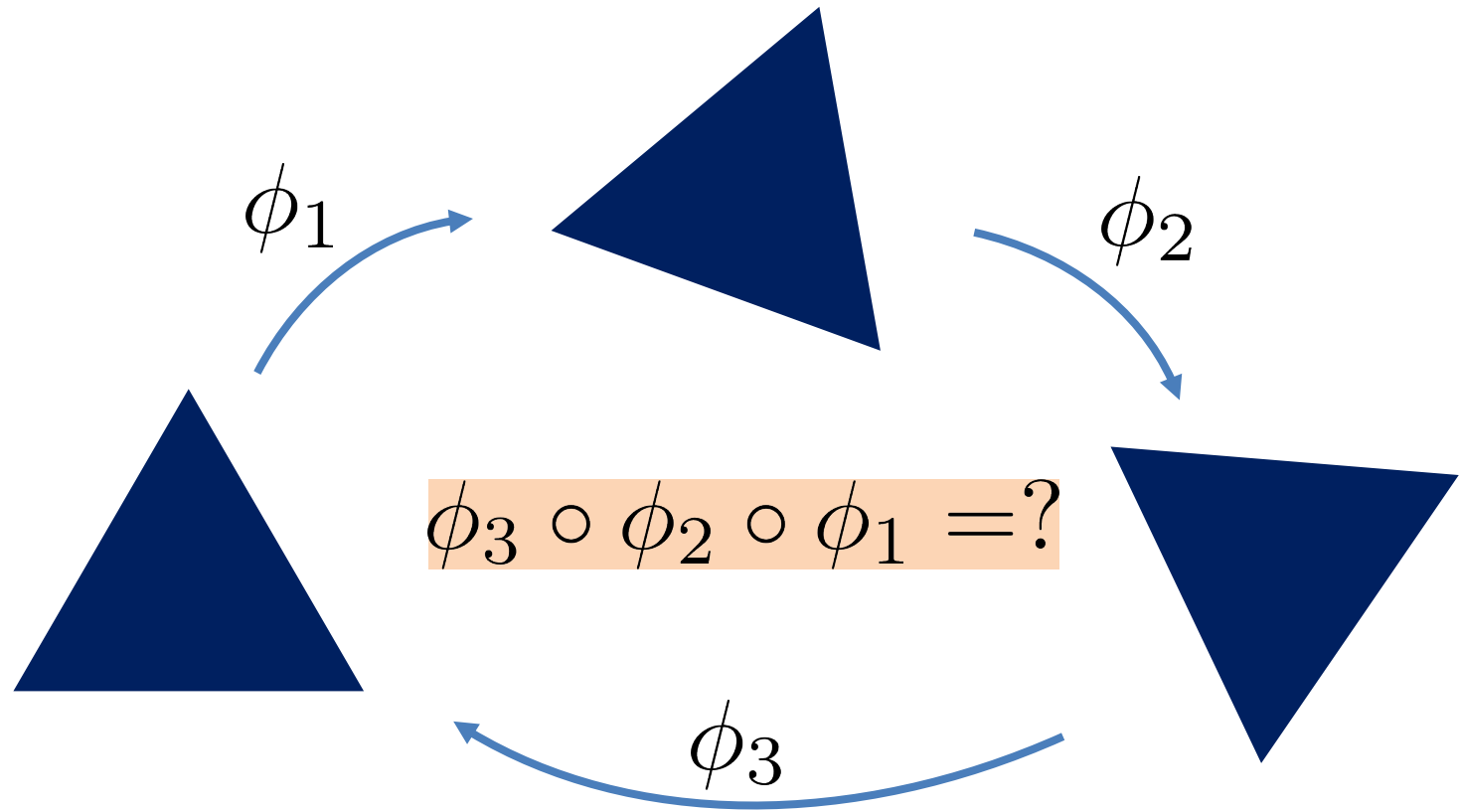


**Translation** in  $xz$  plane  
**Rotation** about  $y$



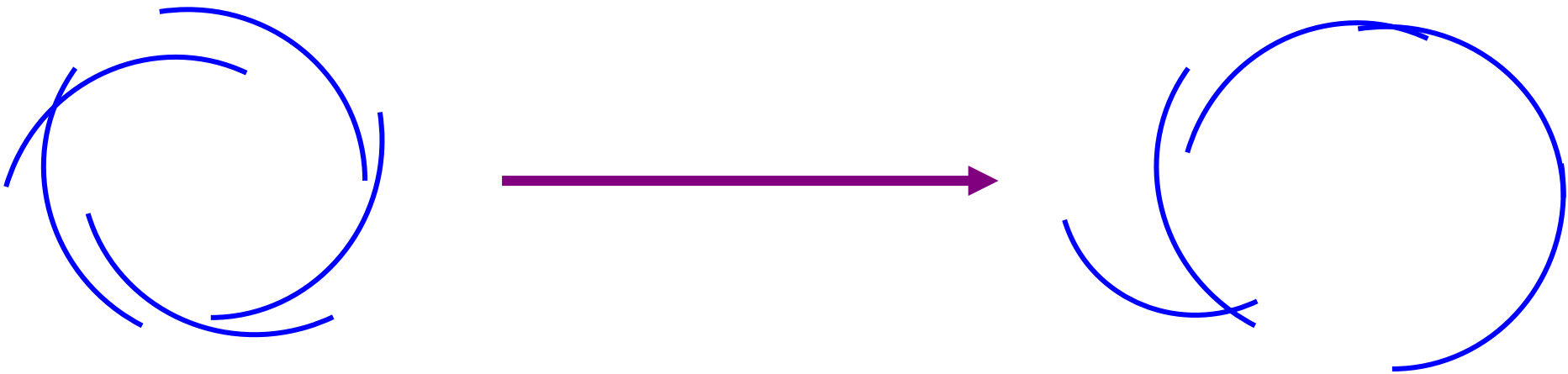
- Converges
- Does not converge

# Issue: ICP Three Times



**Usually have  $\geq 2$  scans**

# Improve Sequential Alignment?

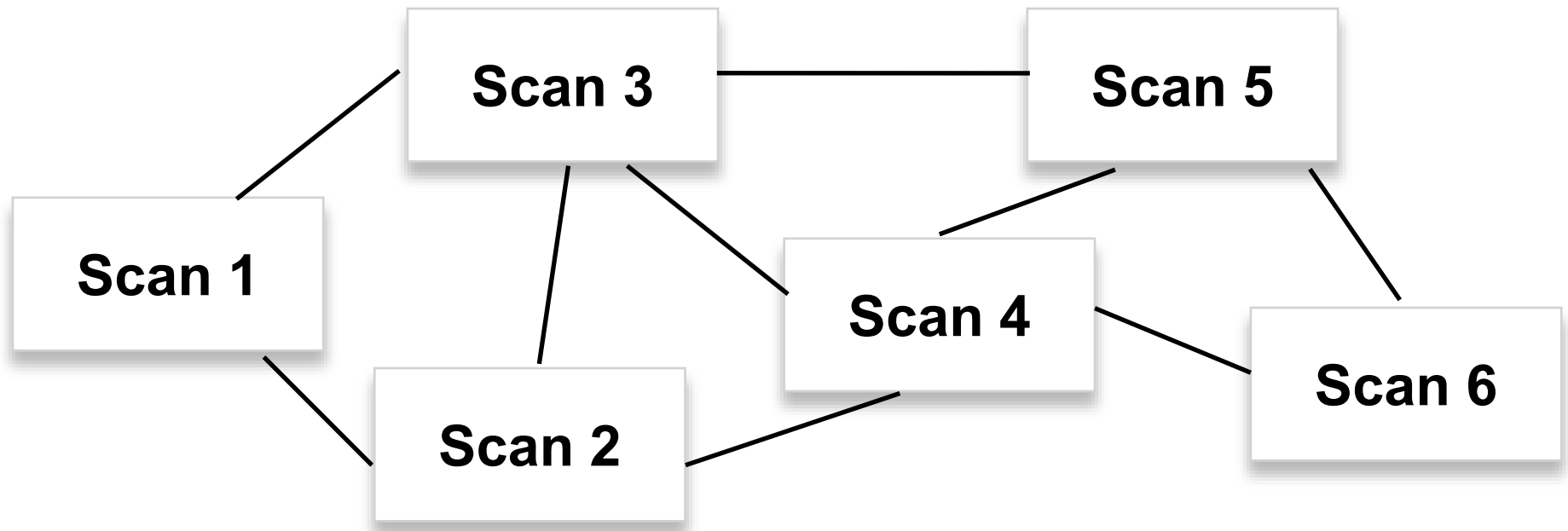


**Prevent “drift”**

# Simple Methods

- **Align everything to *anchor* scan**  
*Which to choose? Dependence on anchor?*
- **Align to *union* of previous scans**  
*Order dependence? Speed?*
- ***Simultaneously* align everything using ICP**  
*Local optima? Computational expense?*

# Graph Approach



**Align similar scans, then assemble**

# Lu and Milios

- **Pairwise phase**

*Compute pairwise ICP on graph*

- **Global alignment**

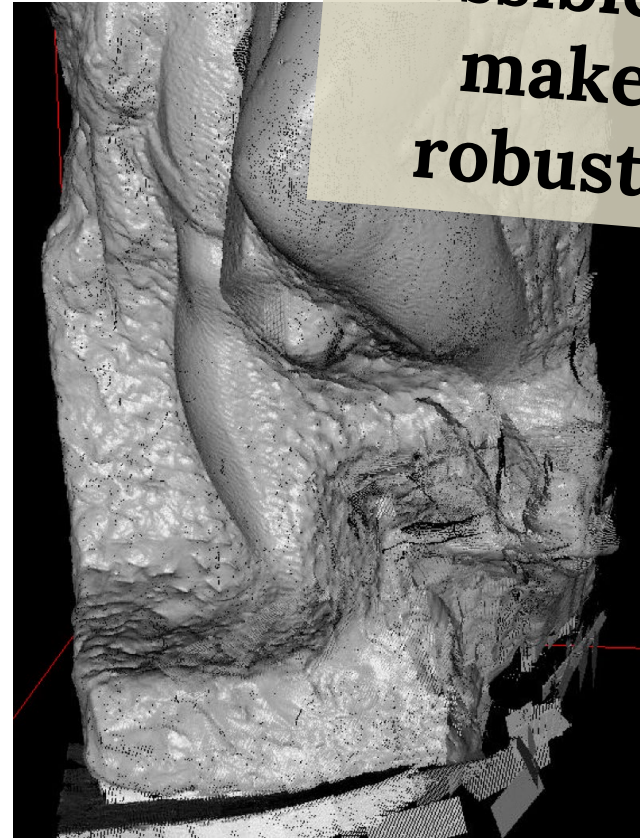
*Least-squares rotation/translation*

**Linearize for  
global alignment**

# Failed ICP in Global Registration

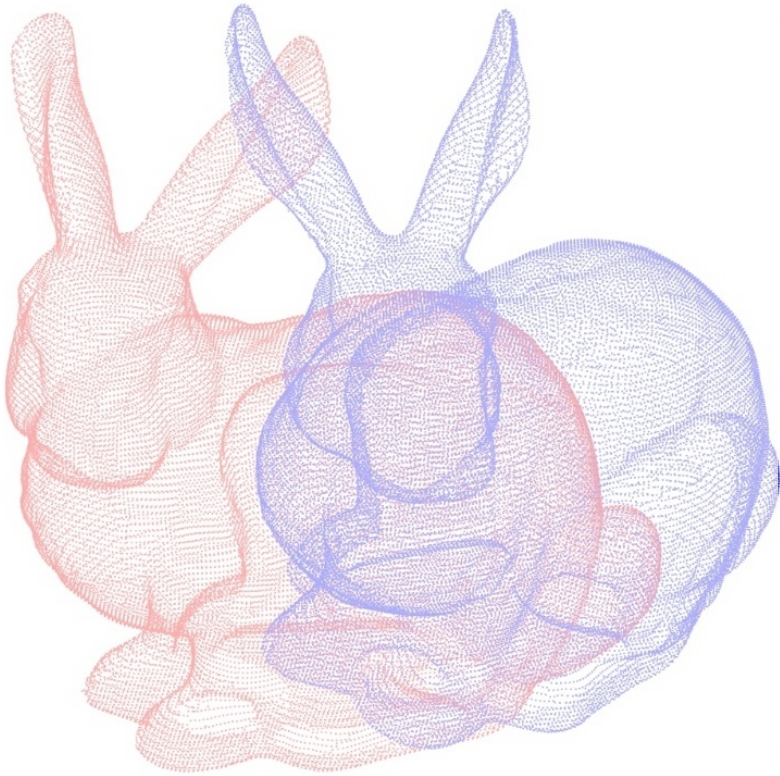


Correct global  
registration



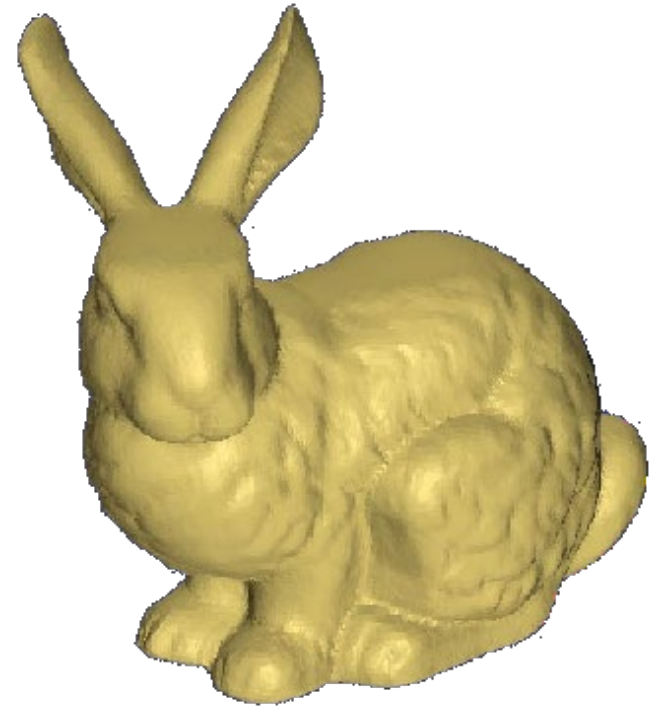
Global registration  
including bad ICP

# Two components



[https://i.ytimg.com/vi/uzOCS\\_gdZuM/maxresdefault.jpg](https://i.ytimg.com/vi/uzOCS_gdZuM/maxresdefault.jpg)

Registration



Meshing

# Triangulating Point Clouds

Connect neighboring points into triangles



Point cloud data



Reconstructed surface



# Triangulating Point Clouds

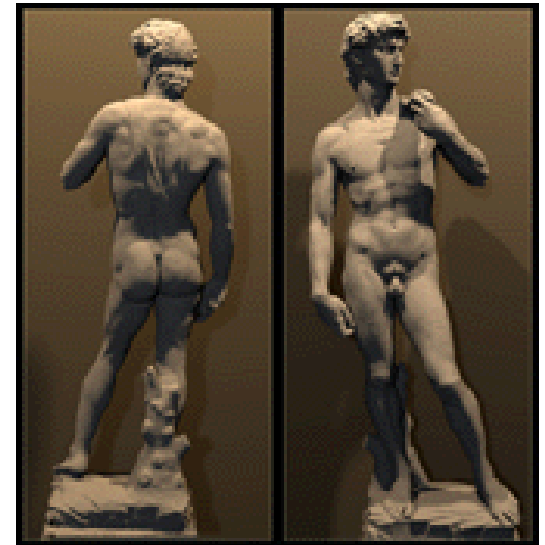
Connect neighboring points into triangles



Point cloud data



Reconstructed surface



Who are the neighbors?

⇔ What's the connectivity/topology

# Methods

- Explicit, *or reconstruction circa 1998*
  - Zippering
  - Delaunay/Voronoi-based
- Implicit
  - Signed distance function
  - Poisson
- Data-driven

# Methods

- Explicit, *or reconstruction circa 1998*
  - **Zippering**
  - Delaunay/Voronoi-based
- Implicit
  - Signed distance function
  - Poisson
- Data-driven

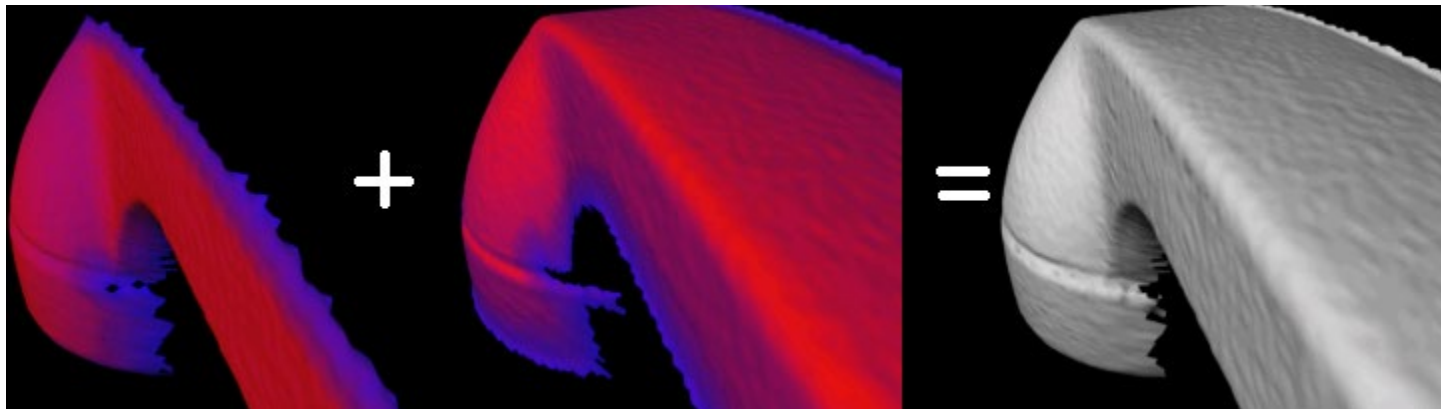
# Basic Reconstruction: Zippering

Single scan  $\rightarrow$  mesh

- regular lattice of points in X and Y with changing depth (Z) = height map

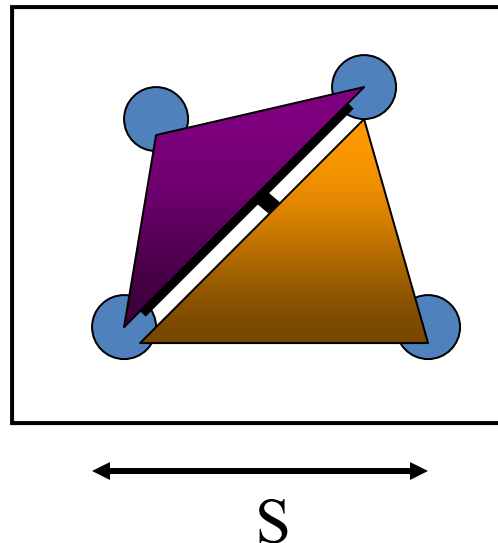
Register

Merge meshes



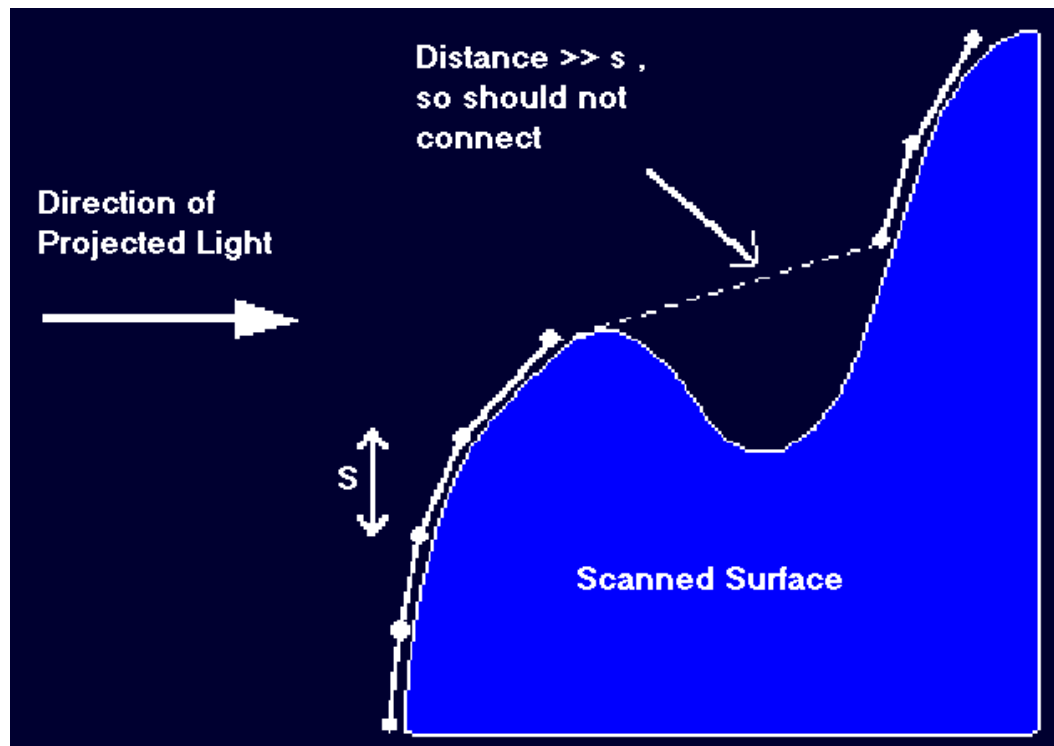
# One scan $\rightarrow$ mesh

- Find quadruples of lattice points
- Form triangles
  - Find shortest diagonal
  - Form two triangles (test depth)



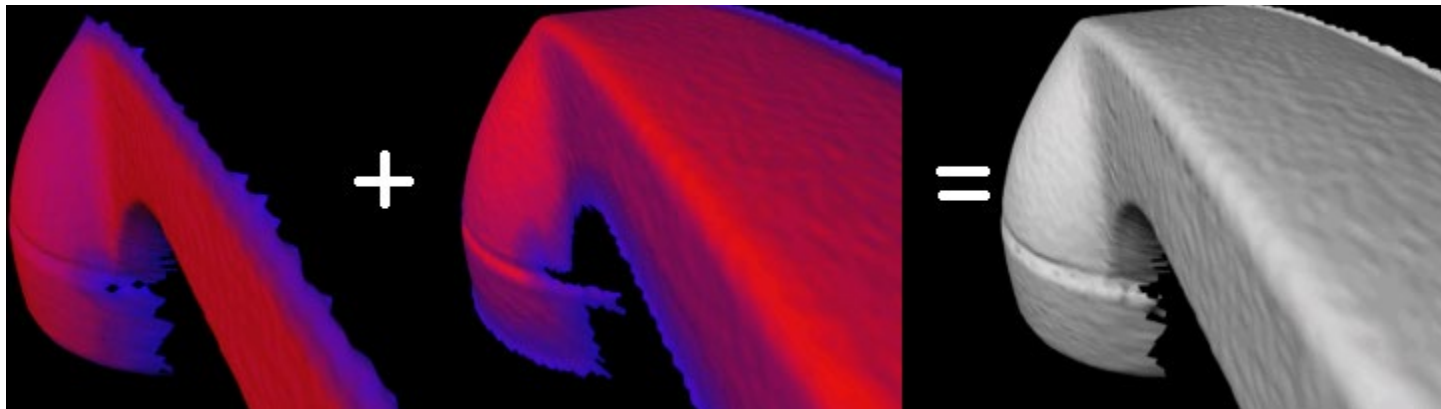
# One scan $\rightarrow$ mesh

## Avoid connecting depth discontinuities



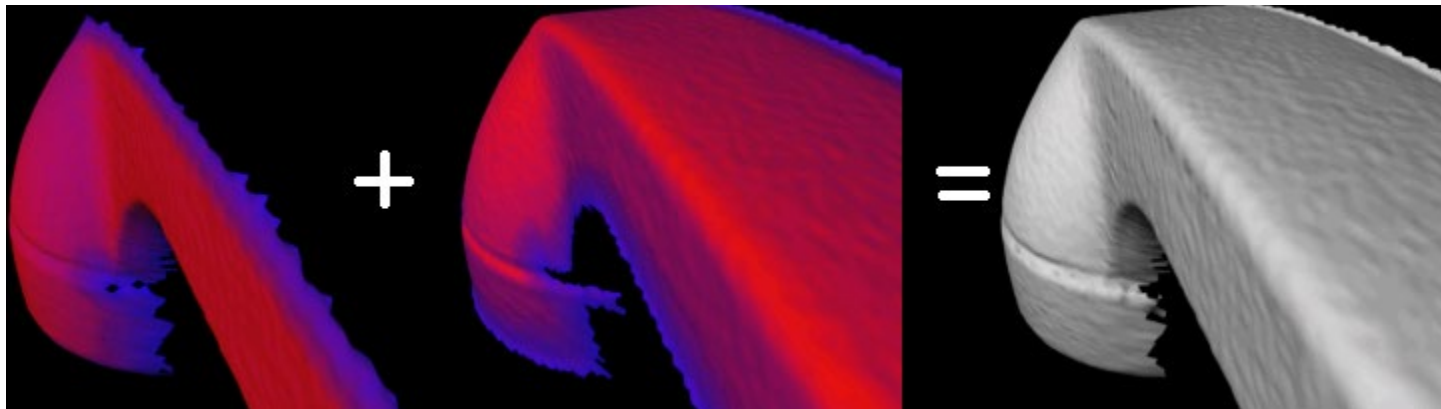
# Basic Reconstruction: Zippering

- ✓ Single scan  $\rightarrow$  mesh
- Register
- Merge meshes



# Basic Reconstruction: Zippering

- ✓ Single scan  $\rightarrow$  mesh
- ✓ Register
- Merge meshes

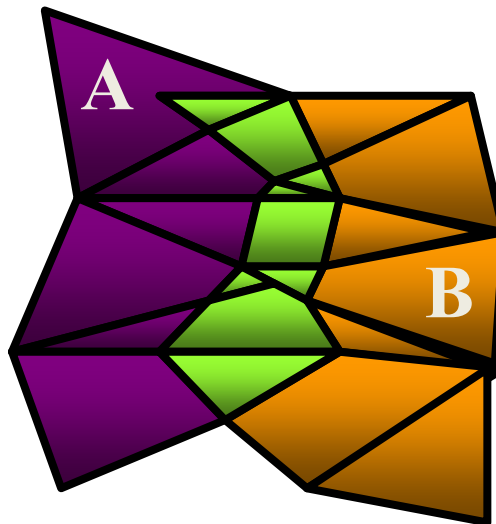


# Merging

2 overlapping meshes

## Zippering

- Remove overlapping portion of the mesh
  - Use for *consensus geometry*
- Clip one mesh against another
- Remove triangles introduced during clipping



# Post-processing



Zippering  
results

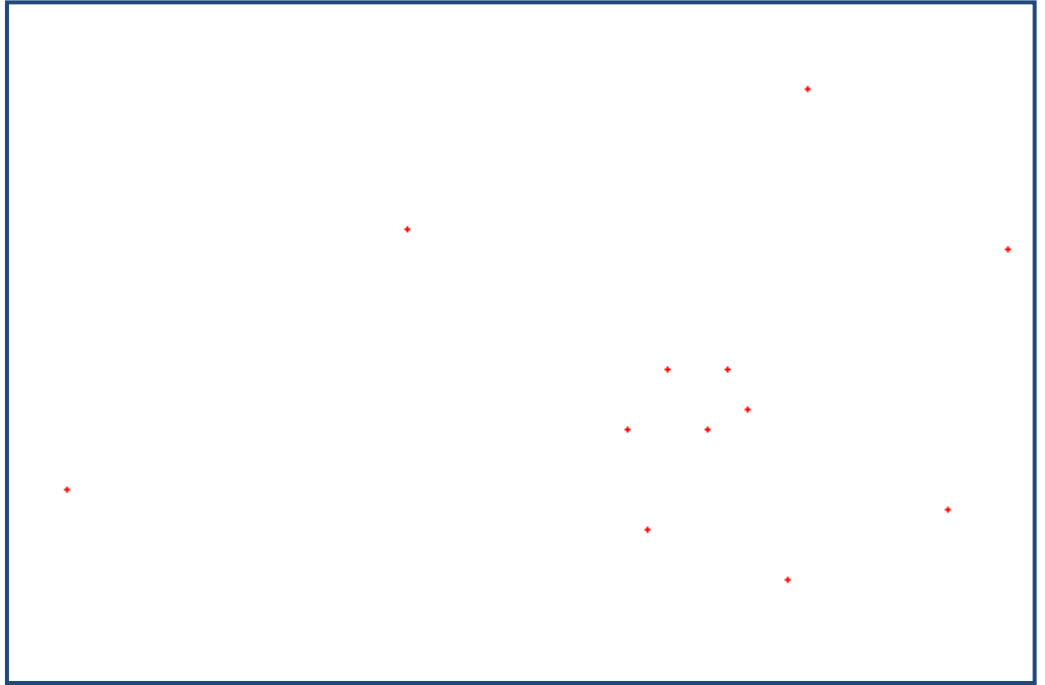
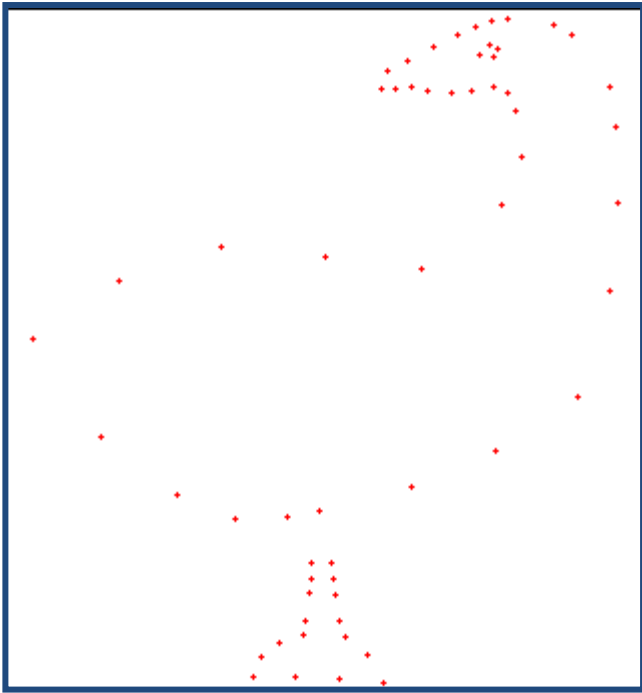
'Consensus  
geometry'

**Move vertices to their average  
positions over all scans**

# Methods

- Explicit, *or reconstruction circa 1998*
  - Zippering
  - **Delaunay/Voronoi-based**
- Implicit
  - Signed distance function
  - Poisson
- Data-driven

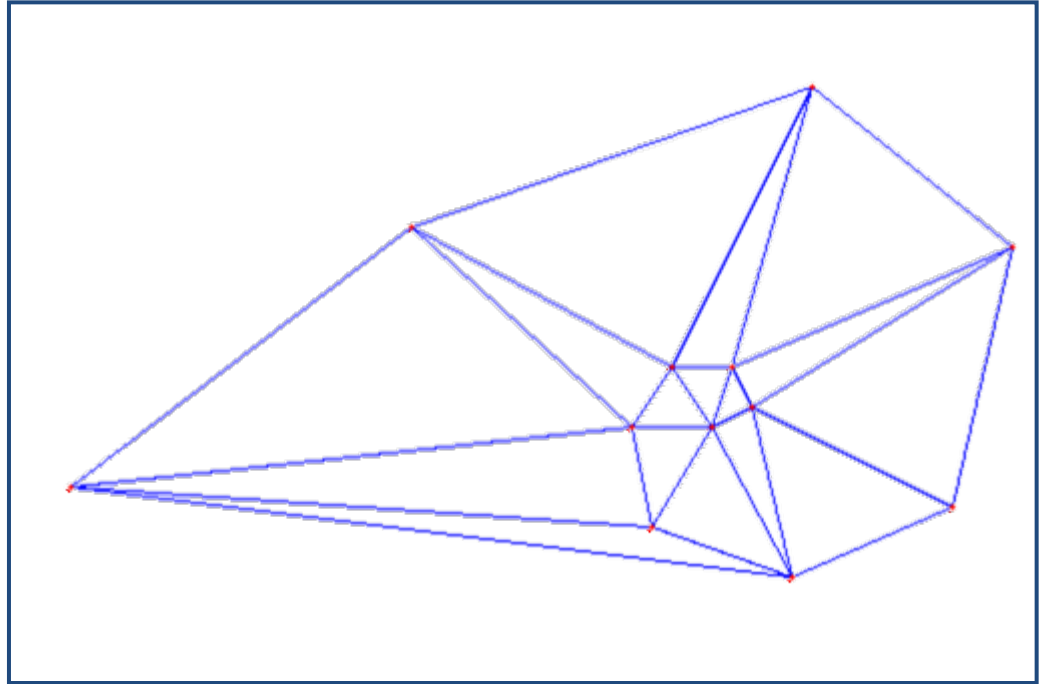
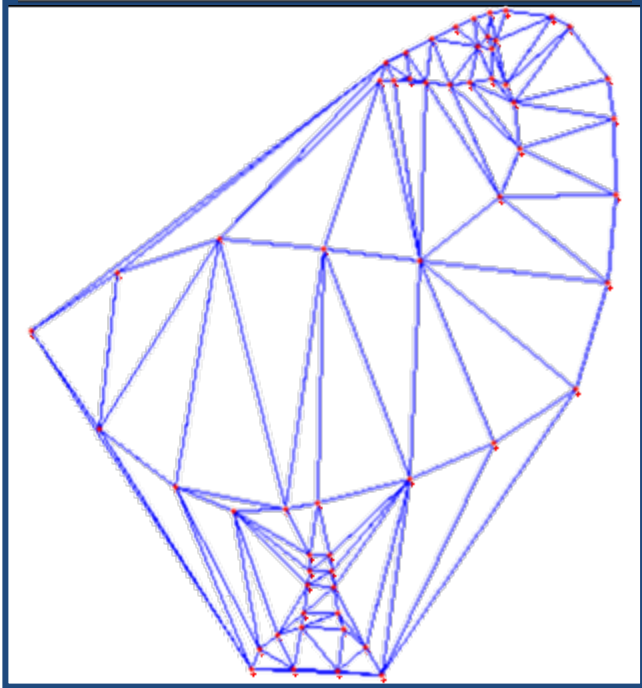
# 2D: connect the dots



Connectivity?

*Edges should be far from other points*

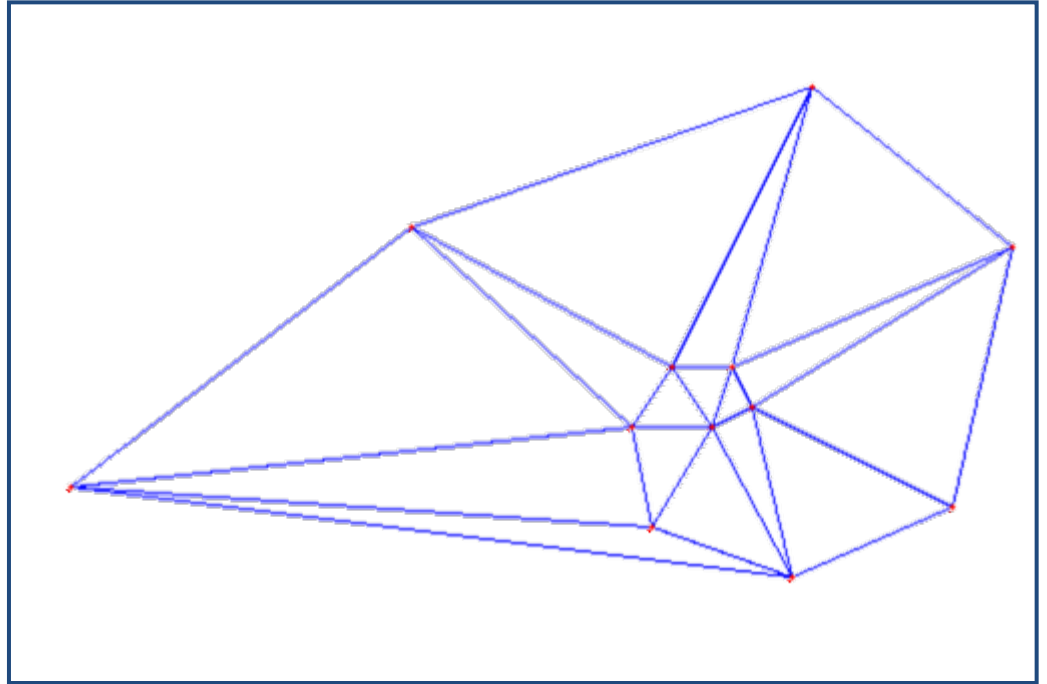
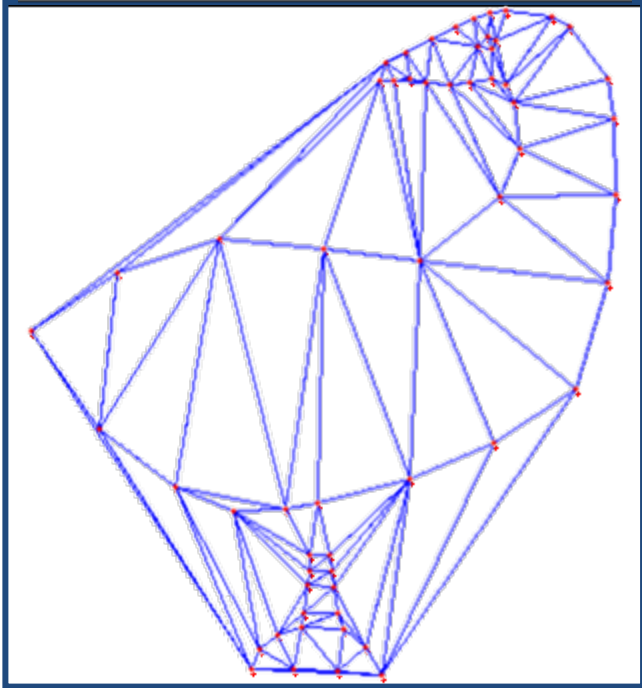
# 2D: connect the dots



## **Delaunay Triangulation**

Edge  $e$  is Delaunay  $\Leftrightarrow$  some circumcircle of  $e$  contains no other sample points

# 2D: connect the dots

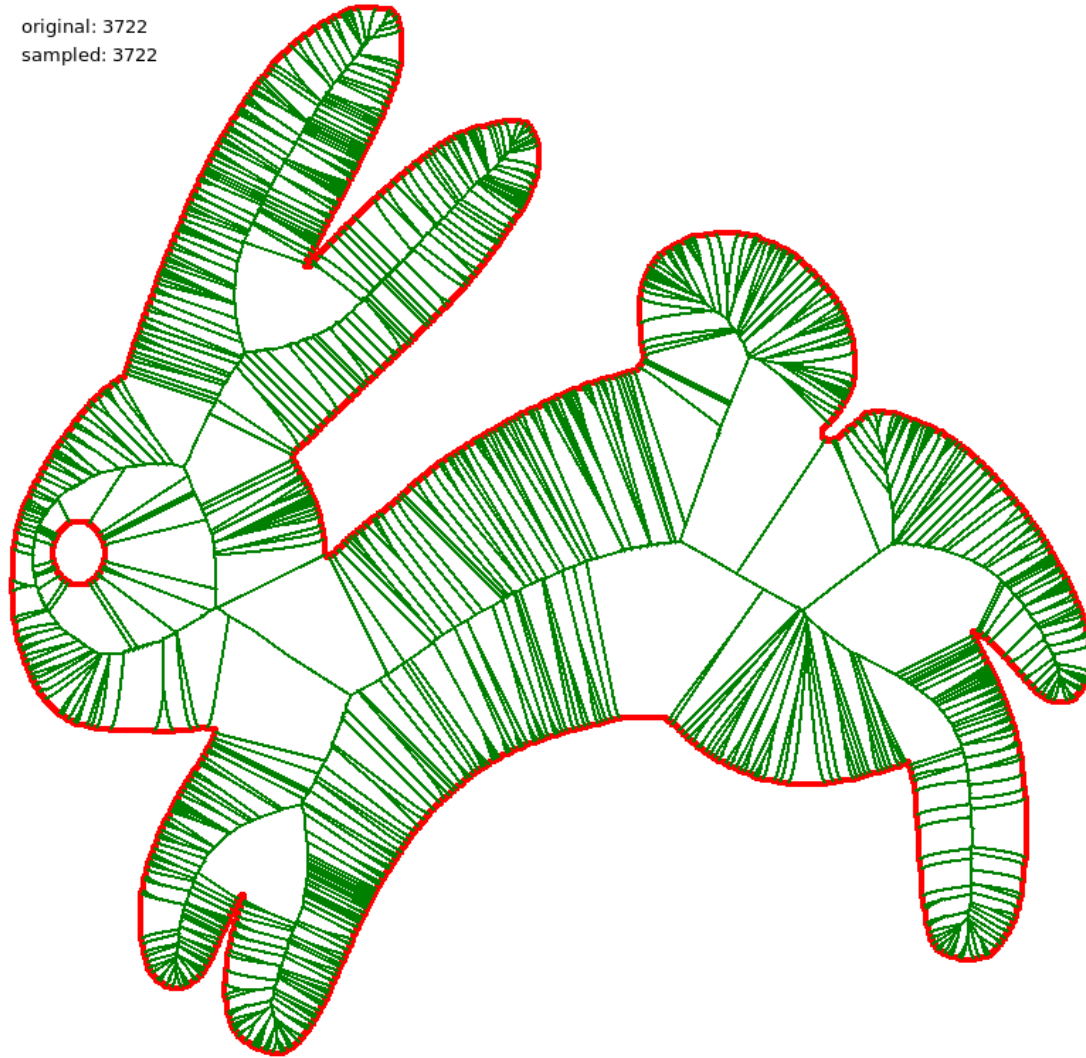


Which edges to pick?

*Recall:*

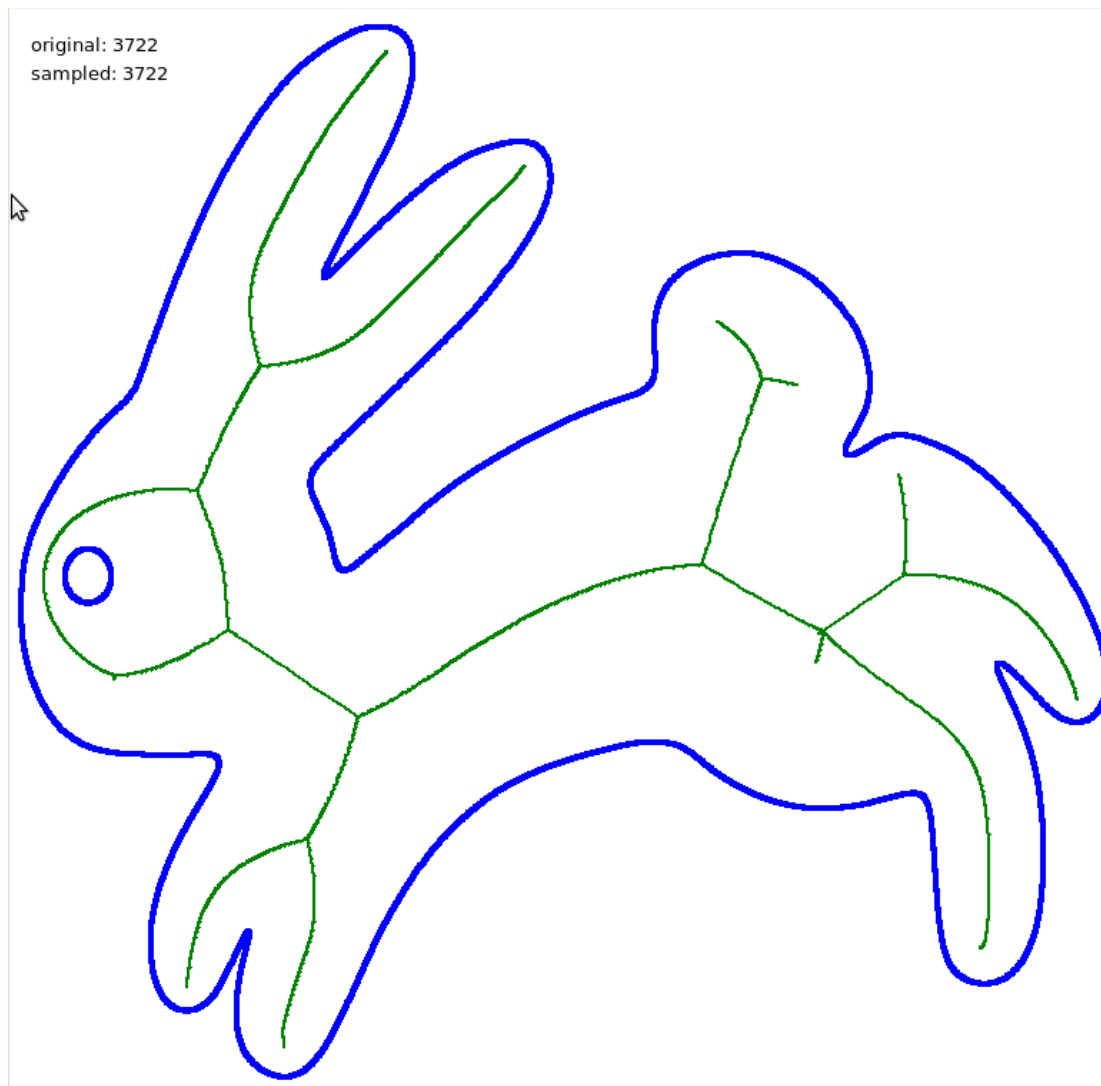
# Medial axis vs Voronoi diagram

original: 3722  
sampled: 3722

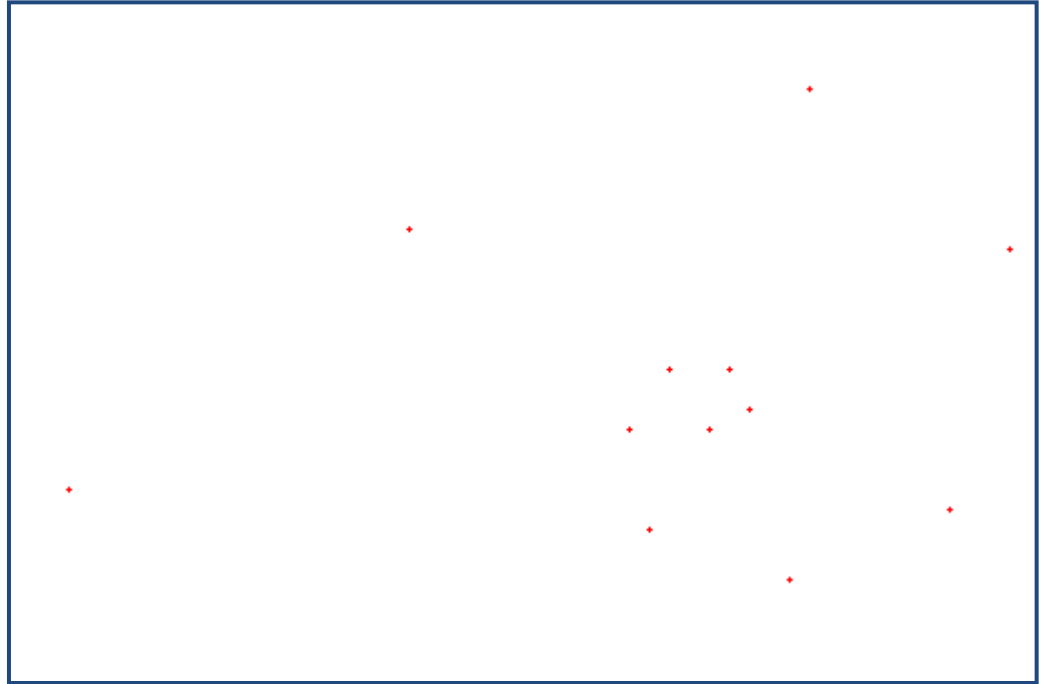
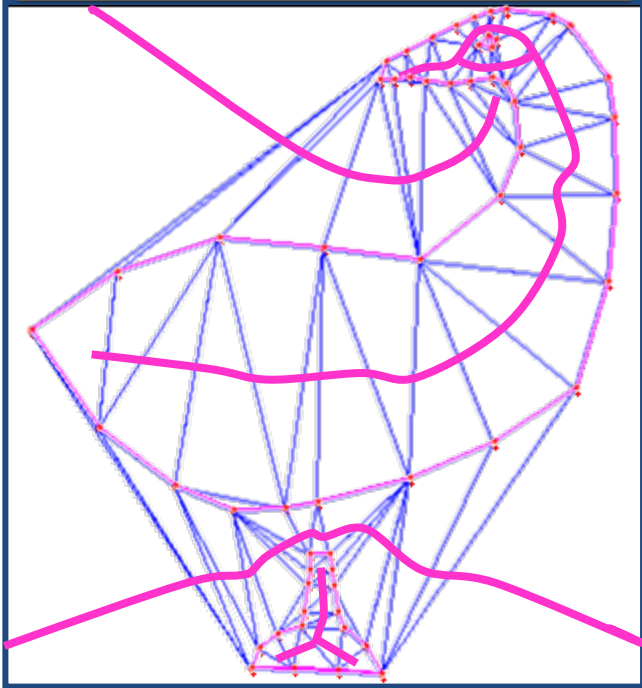


*Recall:*

# Medial axis vs Voronoi diagram

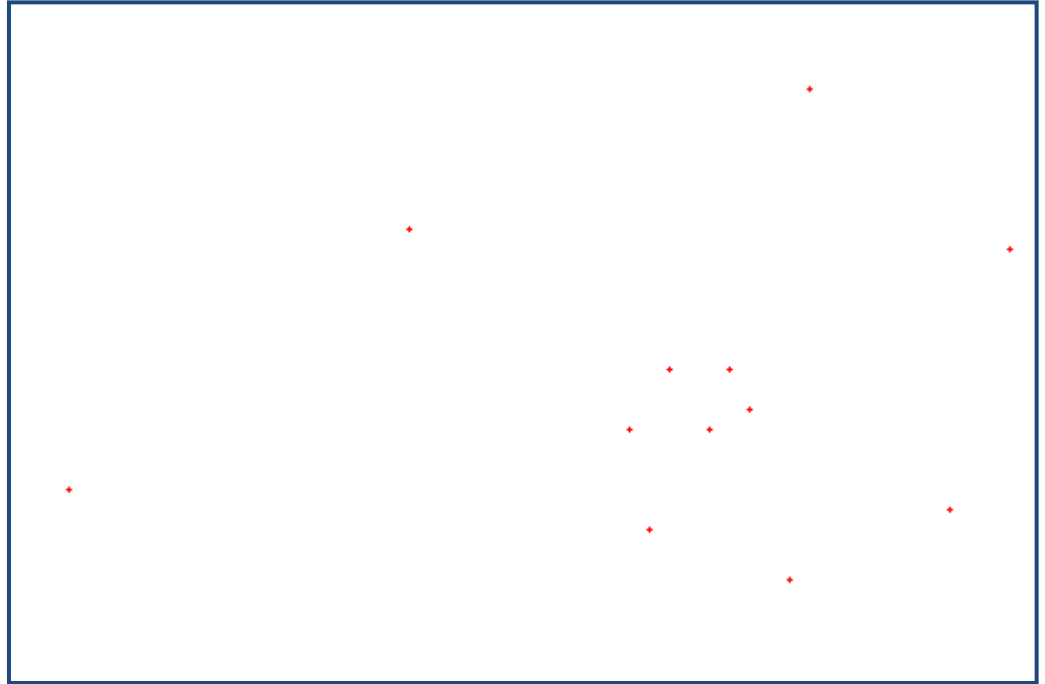
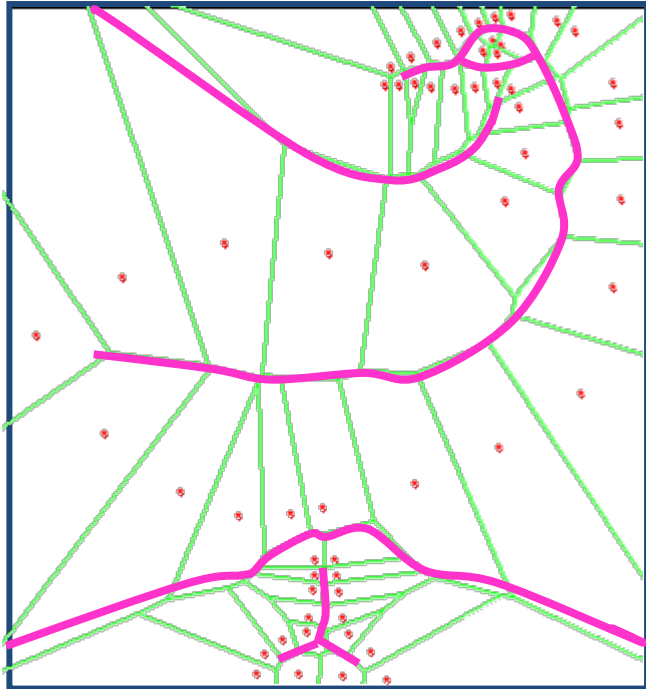


# 2D: connect the dots



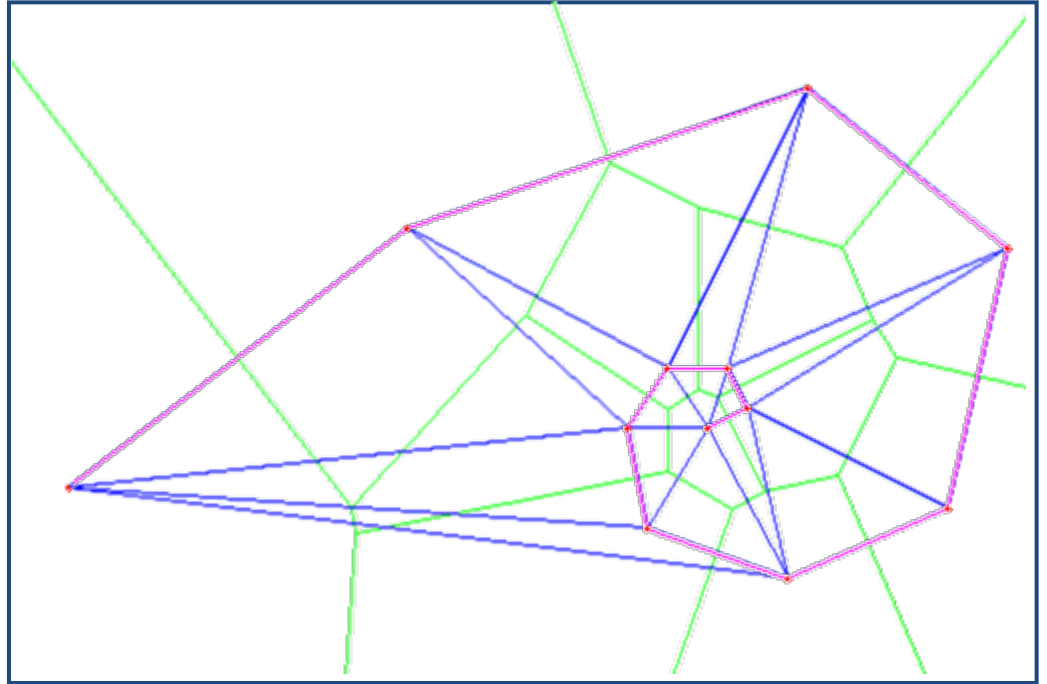
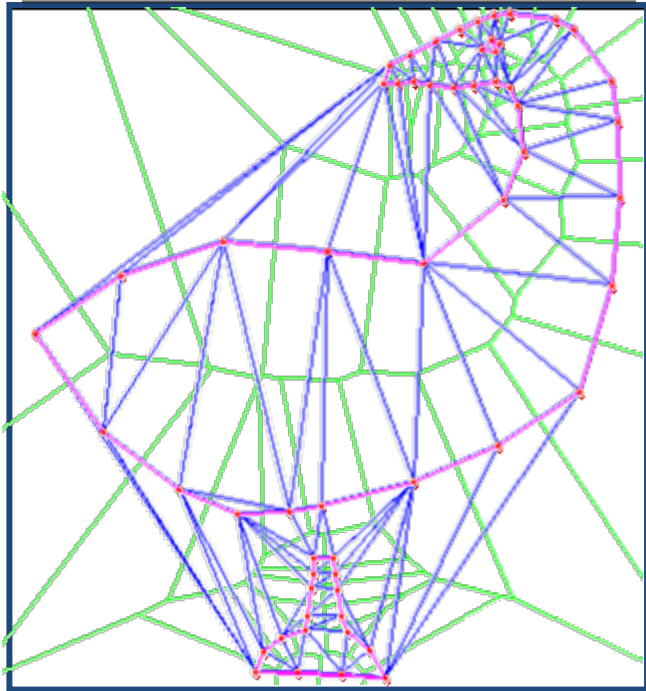
Edges should be “far” from Medial Axis

## 2D: connect the dots



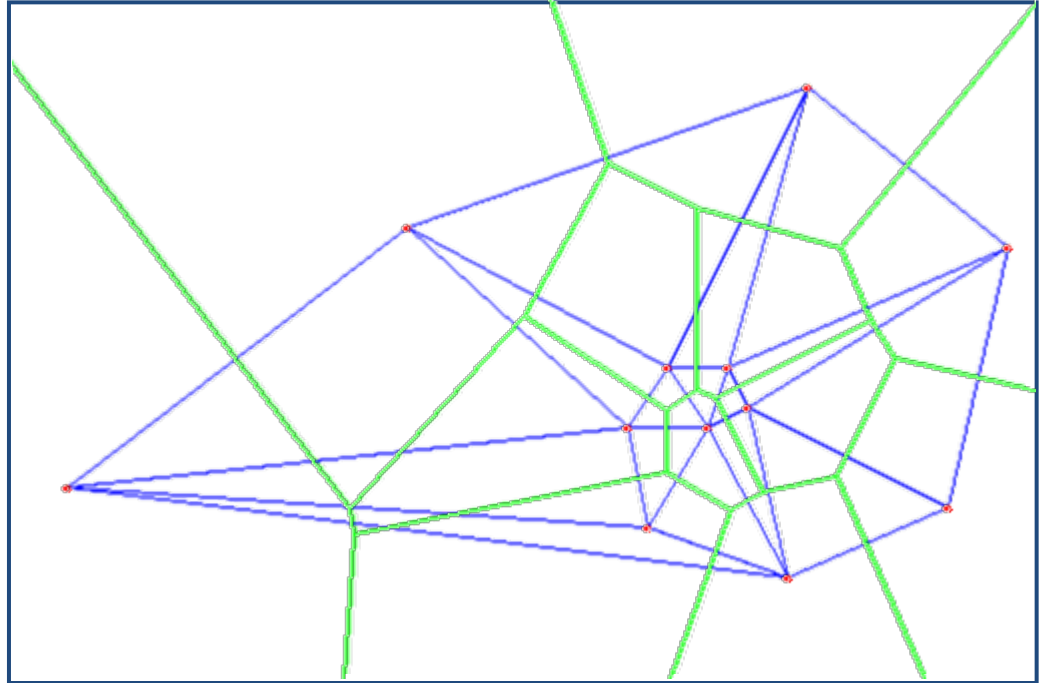
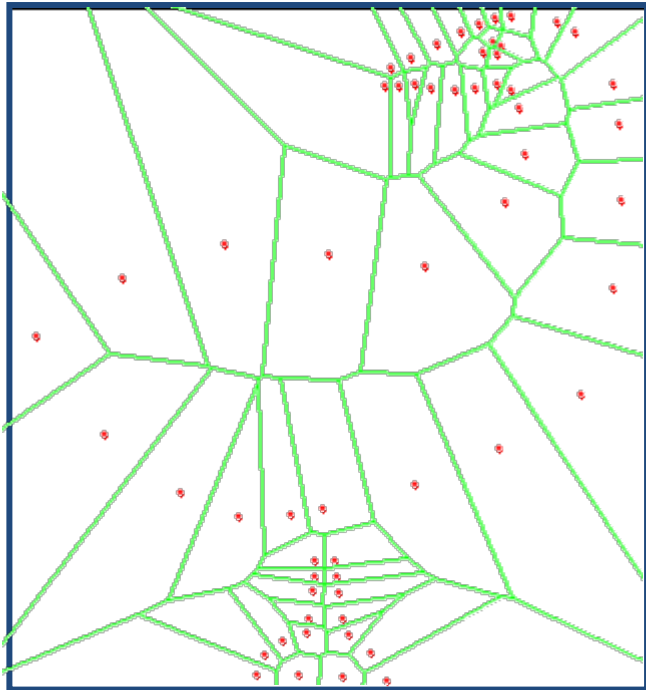
Voronoi diagram approximates Medial Axis  
*if points are sampled densely enough*

## 2D: connect the dots



Edge  $e$  in **crust**  $\Leftrightarrow$   
a circumcircle of  $e$  contains no other  
sample points or Voronoi vertices of  $S$

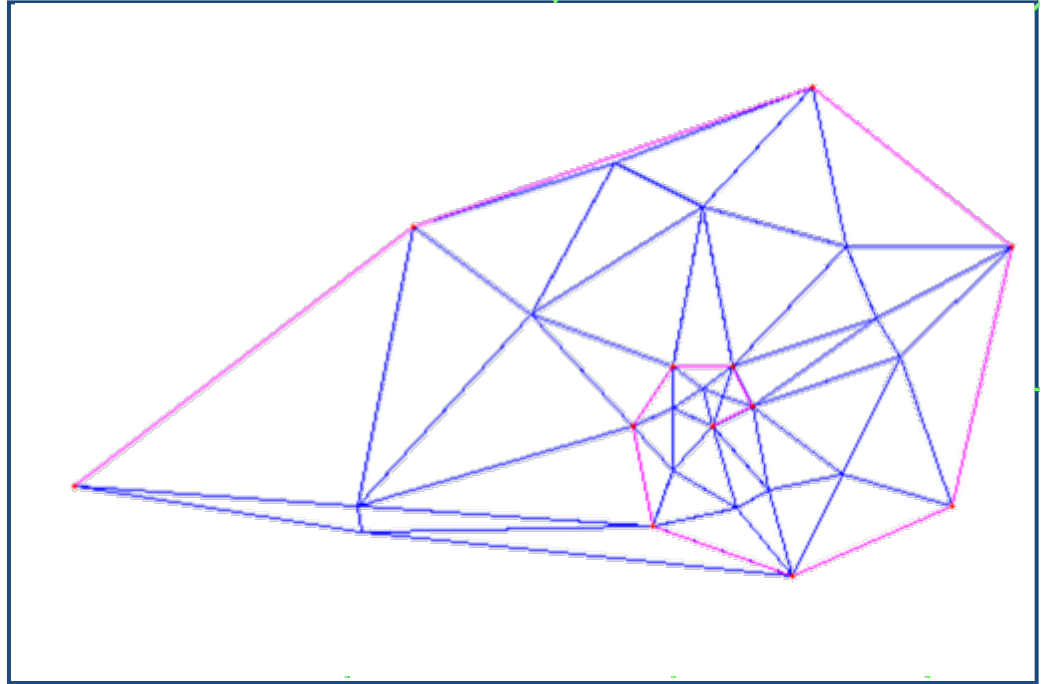
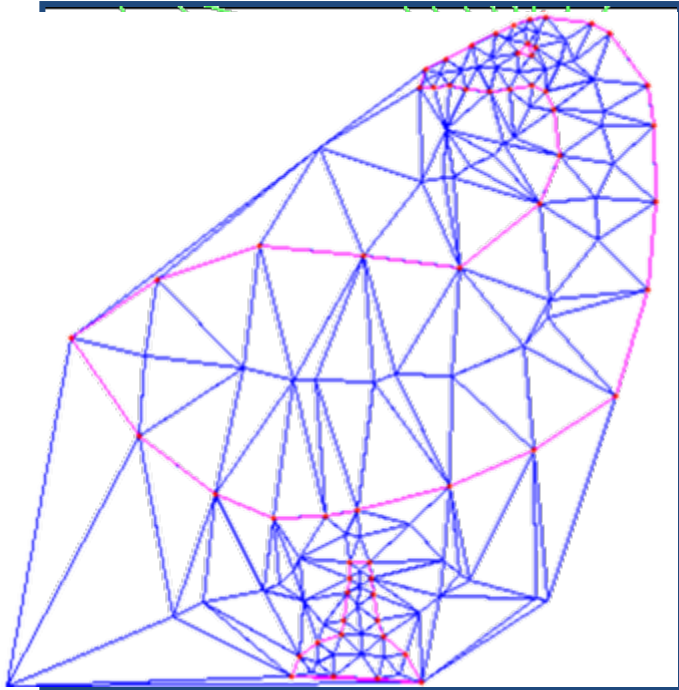
# Crust: Algorithm



Compute Voronoi diagram of  $S$

$V = \{\text{Voronoi vertices}\}$

# Crust: Algorithm

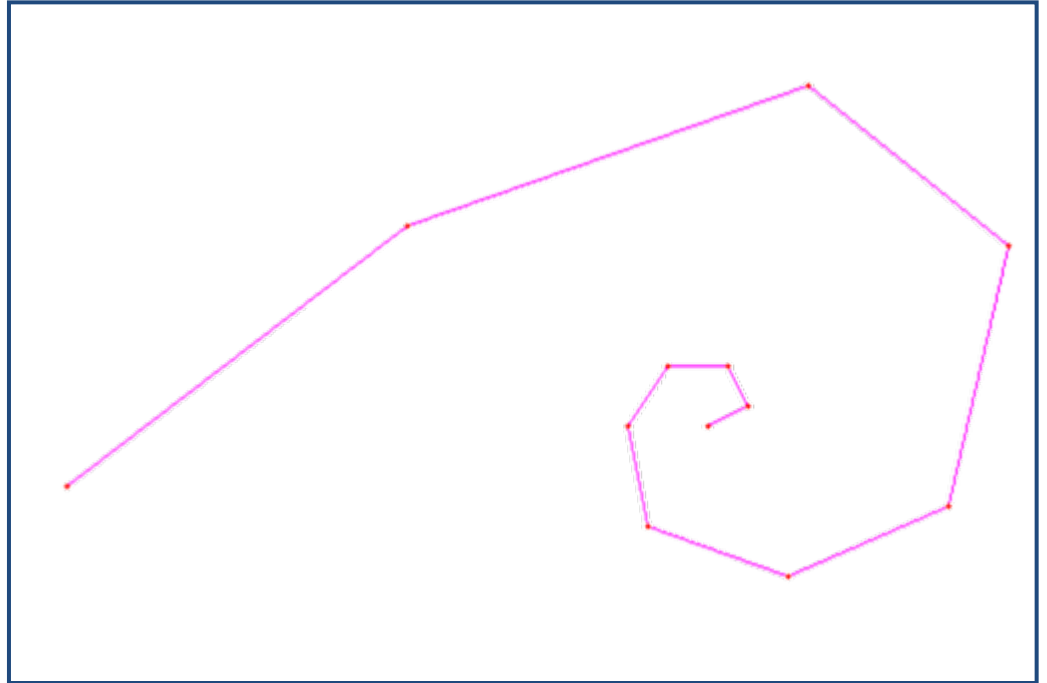
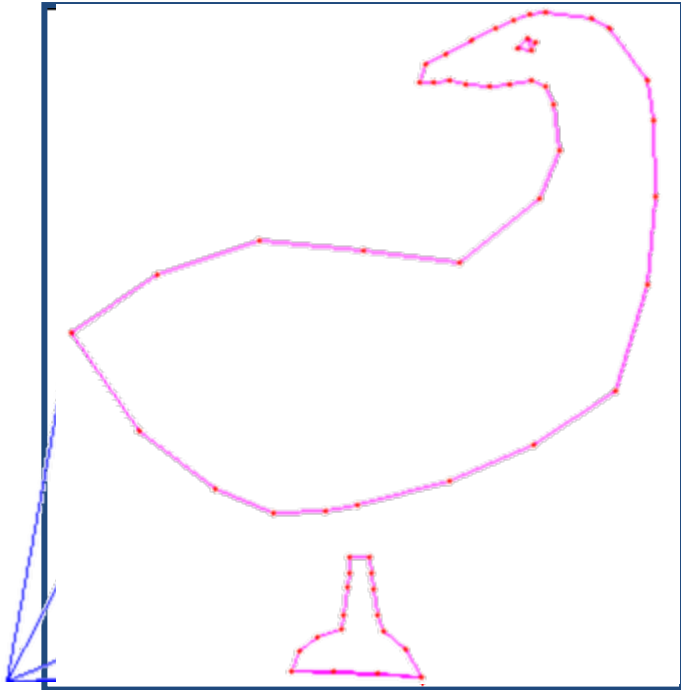


Compute Voronoi diagram of  $S$

$$V = \{\text{Voronoi vertices}\}$$

Compute Delaunay Triangulation of  $S \cup V$

# Crust: Algorithm



Compute Voronoi diagram of  $S$

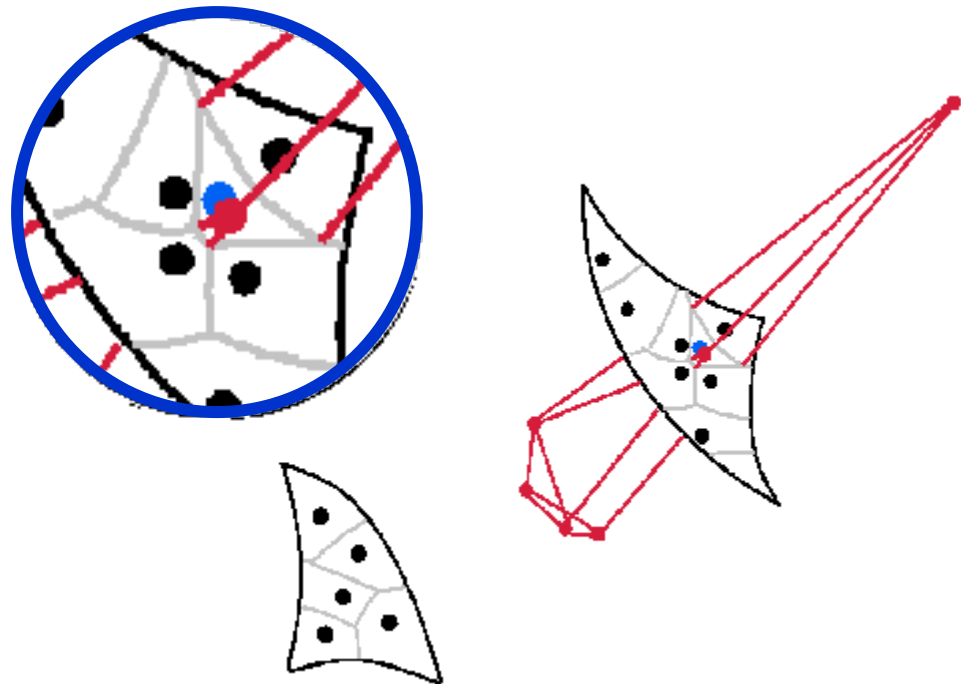
$$V = \{\text{Voronoi vertices}\}$$

Compute Delaunay Triangulation of  $S \cup V$

Crust = all edges between points of  $S$

# 3D Crust Algorithm

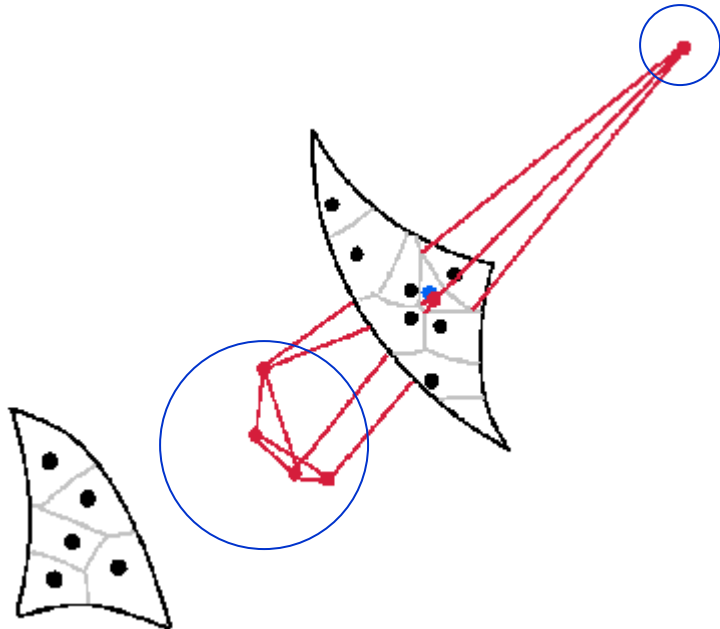
- Extend 2D approach
- Voronoi vertex is equidistant from 4 sample points
- BUT in 3D not all Voronoi vertices are near medial axis (regardless of sampling density)



# 3D Crust Algorithm

**Some** vertices of the Voronoi cell are near medial axis

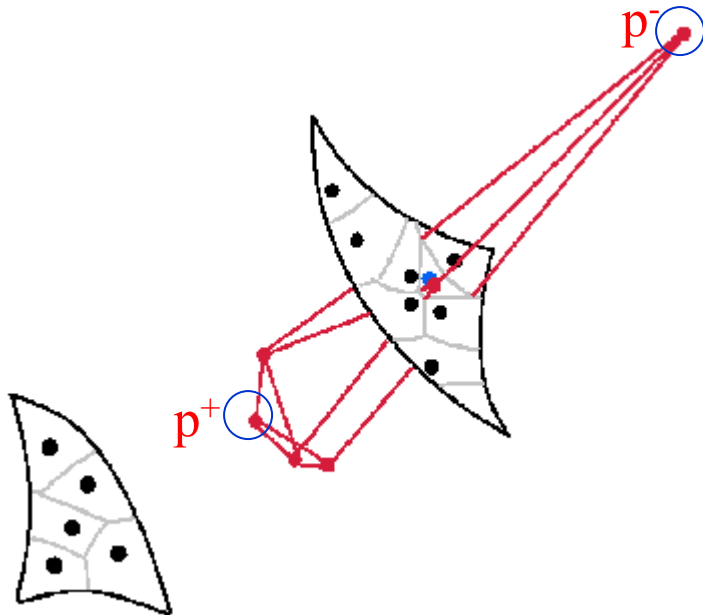
Intuitively – cell is closed not just from the sides but also from “top” & “bottom”



# 3D Crust Algorithm

Solution: use only two farthest vertices of  $V_s$  – one on each side of the surface

- Call vertices *poles* of  $s$  ( $p^+$ ,  $p^-$ )



# 3D Crust Algorithm

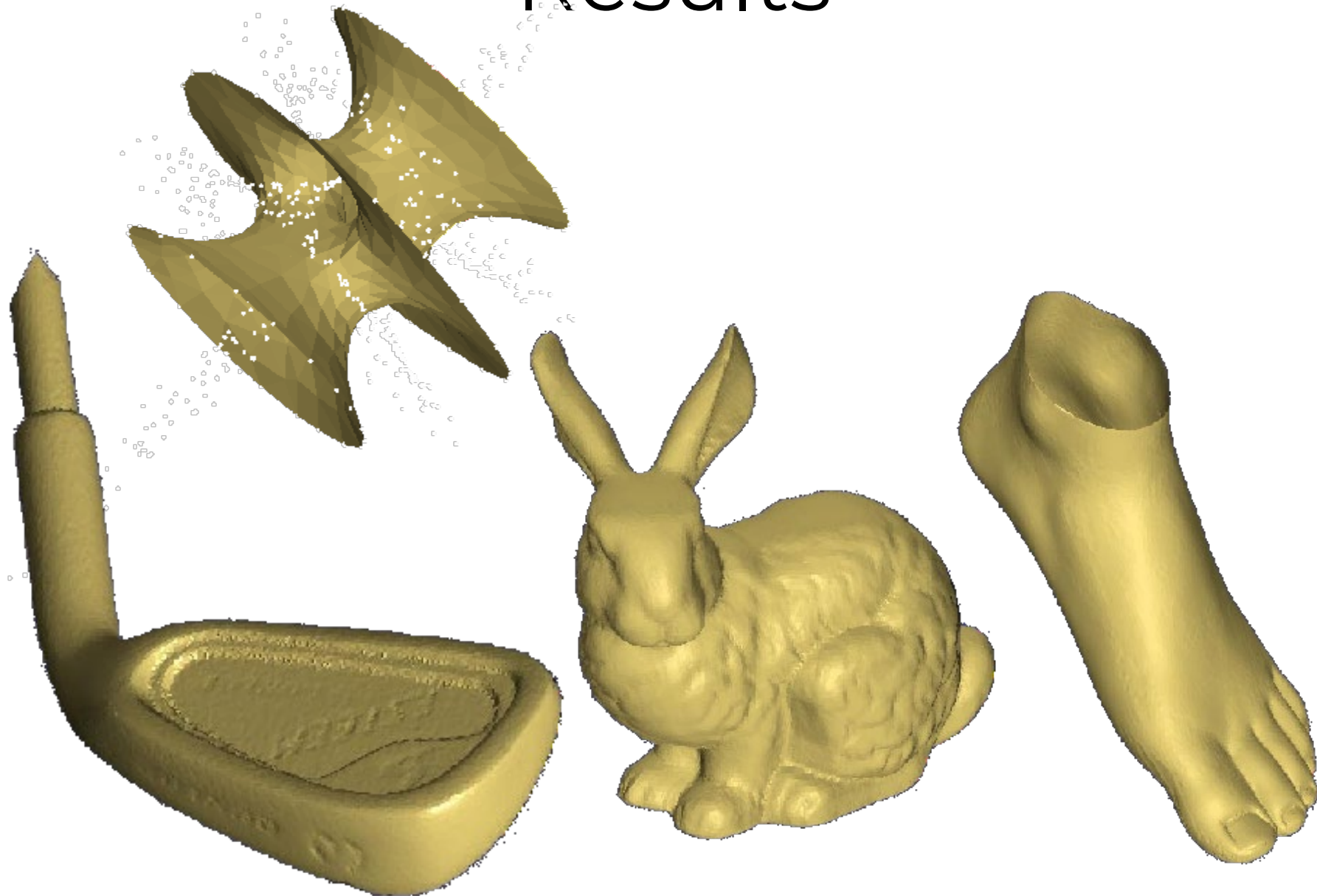
- Compute Voronoi diagram of  $S$
- For each  $s_i \in S$ , compute

$$P = \{p_i^+, p_i^-\}$$

- Compute Delaunay triangulation  $T$  of  $S \cup P$

Crust = all triangles in  $T$  with vertices in  $S$

# Results



# Problems & Modifications

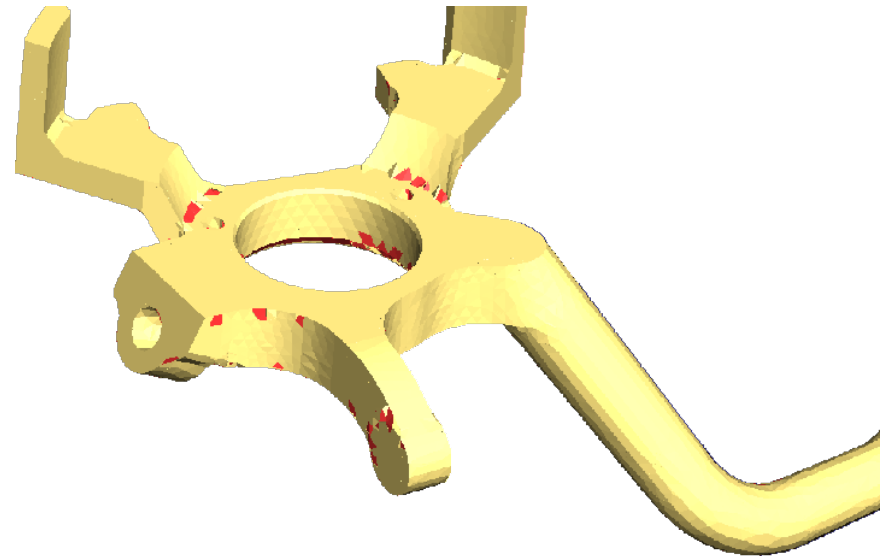
Correct in the absence of noise

Slow-ish

Need dense samples

Problems at sharp corners

Noise

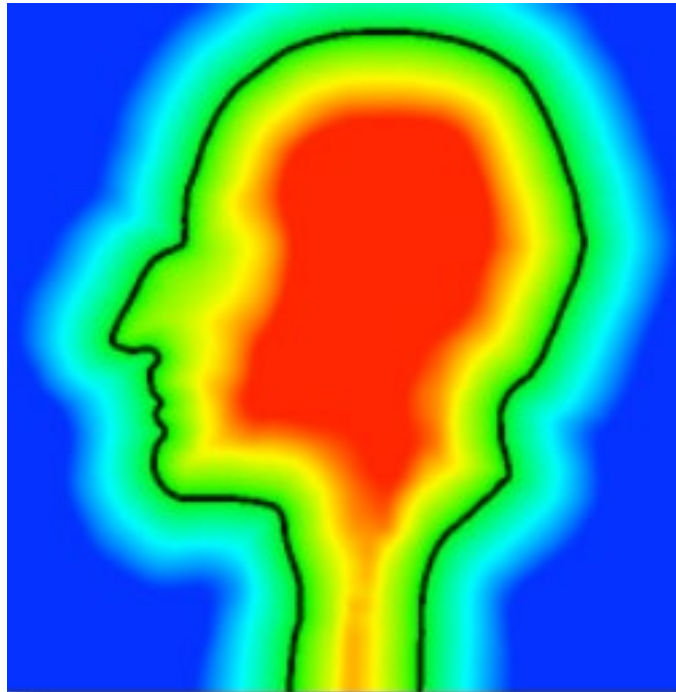


# Methods

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  - Poisson
- Data-driven

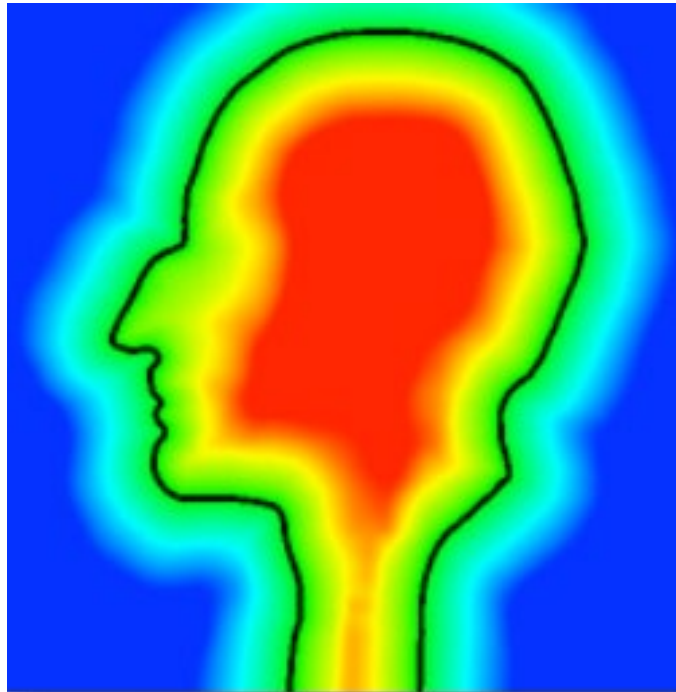
# Implicit Reconstruction

1. Estimate signed distance function  $d: \mathbb{R}^3 \rightarrow \mathbb{R}$
2. Extract an isosurface  $d = 0$



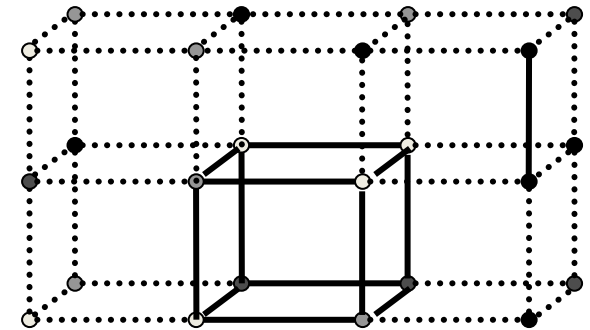
# Implicit Reconstruction

1. Estimate signed distance function  $d: \mathbb{R}^3 \rightarrow \mathbb{R}$
2. **Extract an isosurface  $d = 0$**



# Marching Cubes

- Each voxel:
  - Has values at 8 corners
  - Has 256 possible configurations
    - 15 after counting symmetries and rotations
  - Either
    - Inside isosurface
    - Outside isosurface
    - **Intersects** isosurface
- Can extract triangulation independently per voxel



# Marching Cubes

For each *intersecting* voxel contains triangles of the isosurface

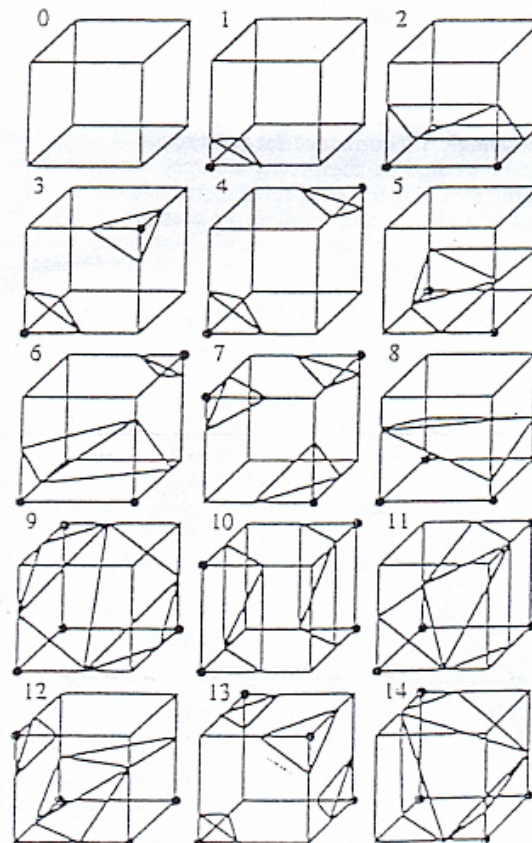
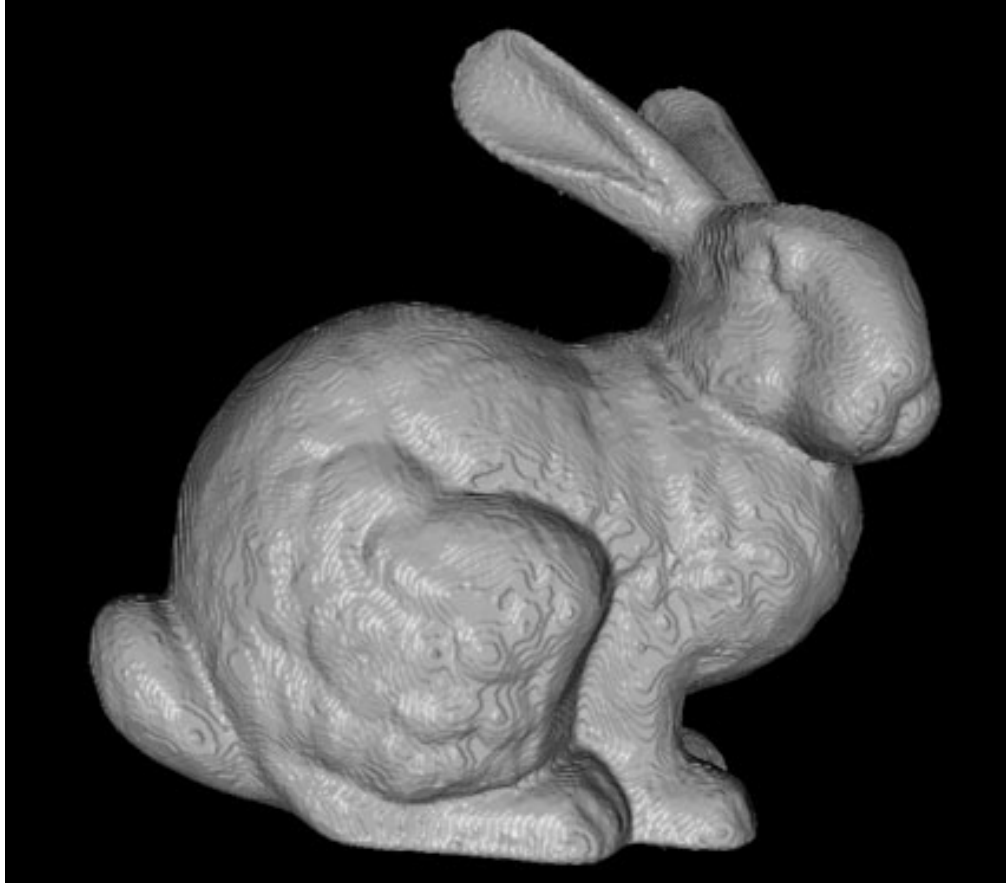


Figure 2. Configurations.

# Configurations

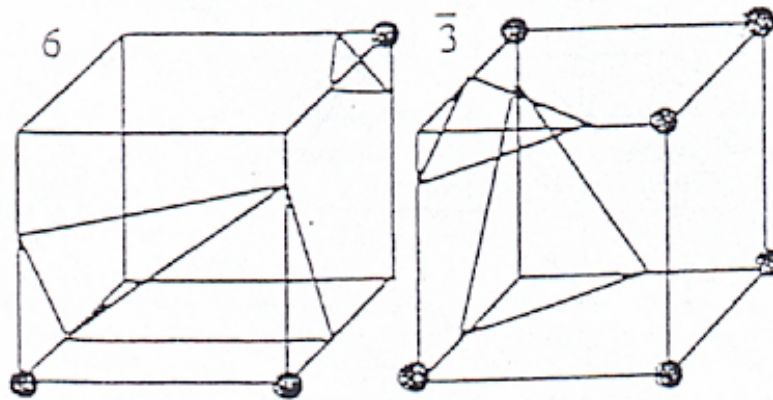
- For each configuration add 1-4 triangles to isosurface
- Isosurface vertices computed by:
  - Interpolation along edges (according to grid values)

# Example



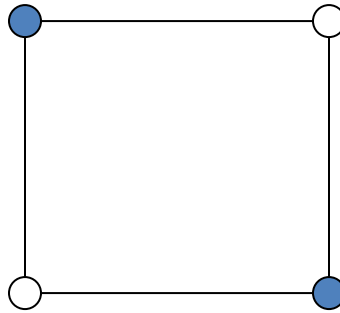
# Problem

Can produce non-manifold results  
and wrong genus

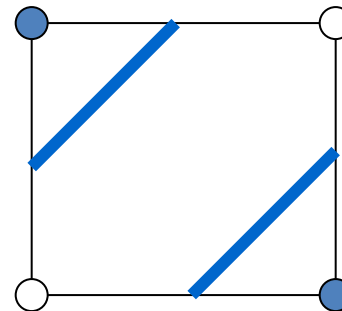
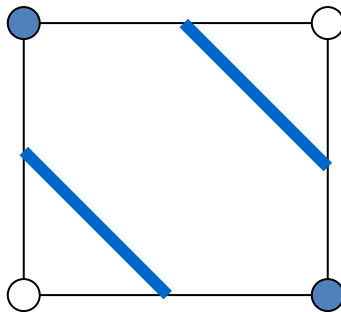


- What if those two are adjacent?
  - Each is ambiguous
- Consistency?

# Ambiguous Faces



- Two locally valid interpretations



- Source of MC consistency problem

# Solution

For those cases, store multiple triangulations

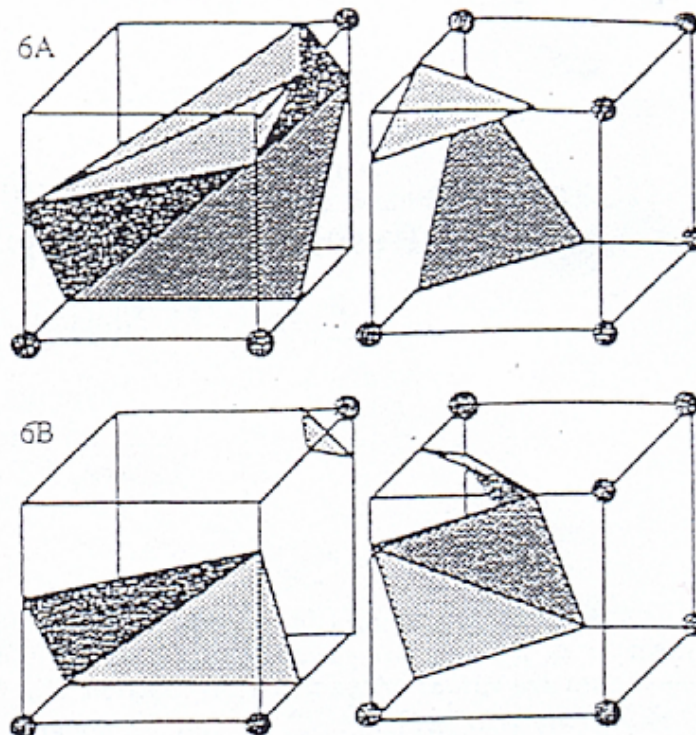


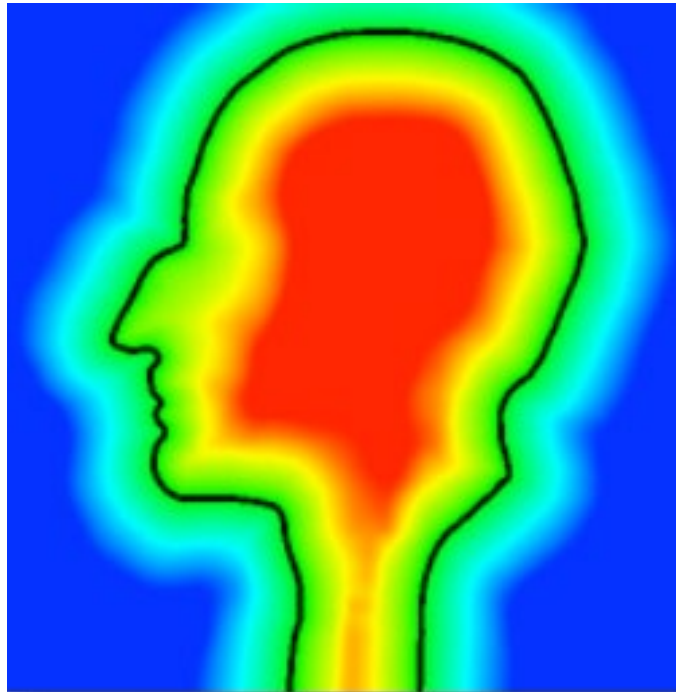
Figure 4. Two possible triangulations which yield a topologically correct isovalue surface.

2.0 Asymptotic Decider

Choose one that agrees with neighbor voxels

# Implicit Reconstruction

1. **Estimate signed distance function  $d: \mathbb{R}^3 \rightarrow \mathbb{R}$**
2. Extract an isosurface  $d = 0$



# Signed distance function

Distance to points is not enough

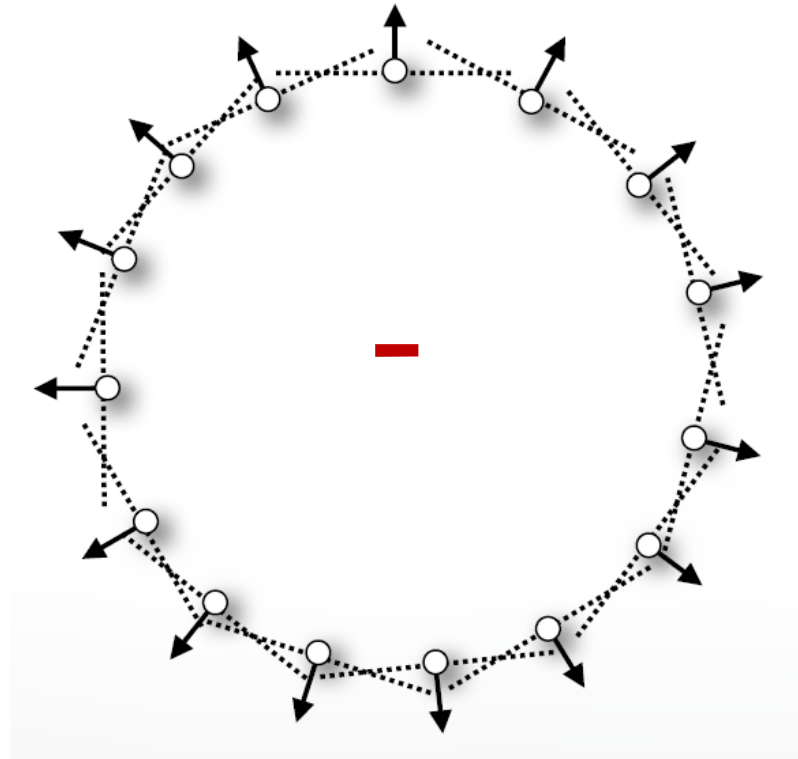
*Need more structure*



# Signed distance function

How can we tell inside from outside?

*Estimate normals.*



# Estimating normals

- Fit a plane into neighborhood of each point
  - Neighborhood =  $k$  nearest neighbors
- Determine *consistent* normal orientation



# Estimating normals

- Fit a plane into neighborhood of each point
  - Neighborhood =  $k$  nearest neighbors
    - Use spatial decompositions (BSP-trees)
- Determine *consistent* normal orientation



# Fitting plane

$$\min_{c \in \mathbb{R}^3, \|n\|=1} \sum_i (n^T (p_i - c))^2$$

On the board, time permitting

# Estimating normals

- Fit a plane into neighborhood of each point
  - Neighborhood =  $k$  nearest neighbors
- Determine *consistent* normal orientation



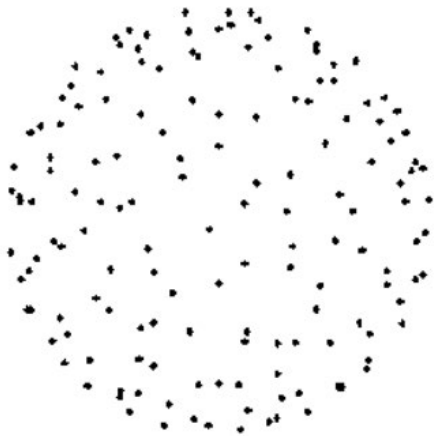
# Estimating normals

- Fit a plane into neighborhood of each point
  - Neighborhood =  $k$  nearest neighbors
- Determine *consistent* normal orientation
  - Make sure  $n_i \cdot n_j > 0$  for neighbors



# Signed Distance Function

- Distance to tangent planes
  - [Hoppe et al. '92]



150 samples



reconstruction  
on  $50^3$  grid

# Signed Distance Function

- Smoother: RBF basis



Hoppe '92



Compact RBF  
Wendland  $C^2$



Global RBF  
Triharmonic

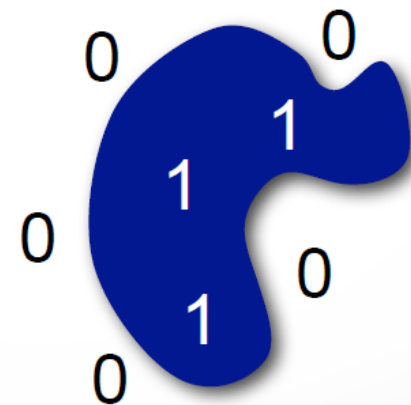
# Signed Distance Function

- Poisson surface reconstruction
  - [Kazhdan et al. '06]

# Signed Distance Function

- Poisson surface reconstruction
  - Solve for indicator function

$$\chi_M(p) = \begin{cases} 1 & \text{if } p \in M \\ 0 & \text{if } p \notin M \end{cases}$$

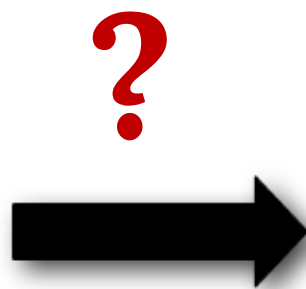


Indicator function

$\chi_M$



Oriented points



Indicator function

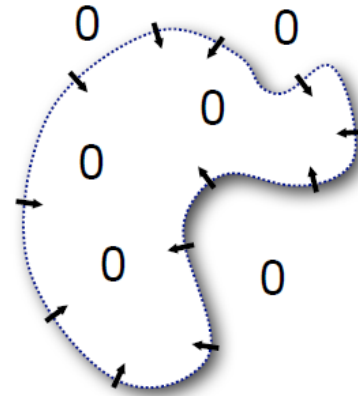
$$\chi_M$$

# Idea

Oriented normals =  
*gradient of an indicator function?*



Oriented points



Indicator gradient

$$\nabla \chi_M$$

# Idea

Oriented normals  $\Rightarrow$  vector field  $\vec{V}$

Find indicator function:

$$\min_{\chi} \|\vec{V} - \nabla \chi\|^2$$

# Idea

Oriented normals  $\Rightarrow$  vector field  $\vec{V}$   
Find indicator function:

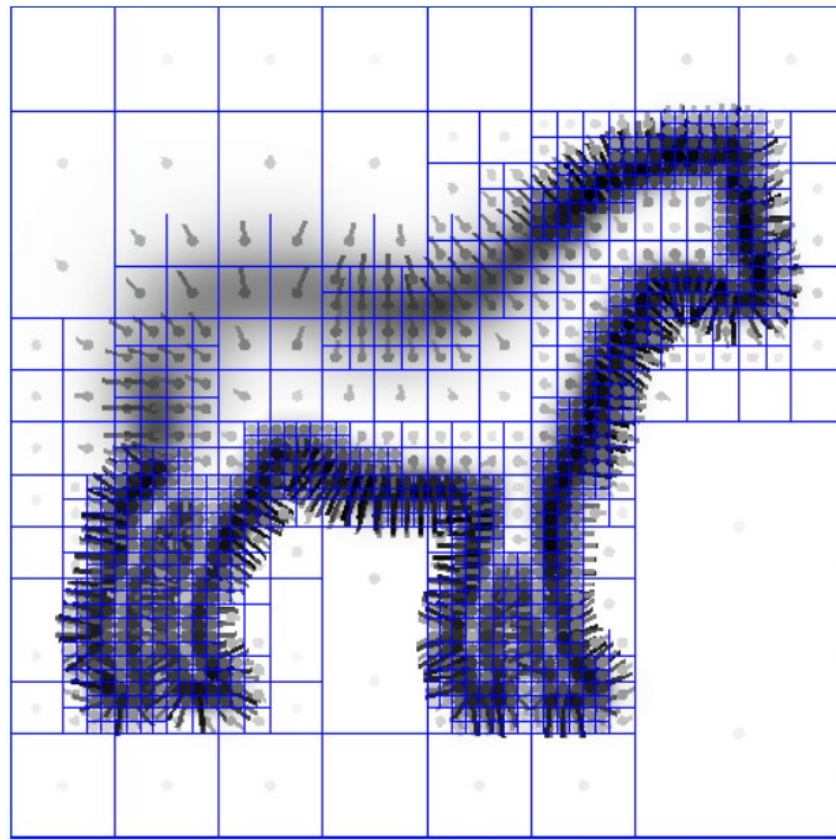
$$\min_{\chi} \|\vec{V} - \nabla \chi\|^2$$

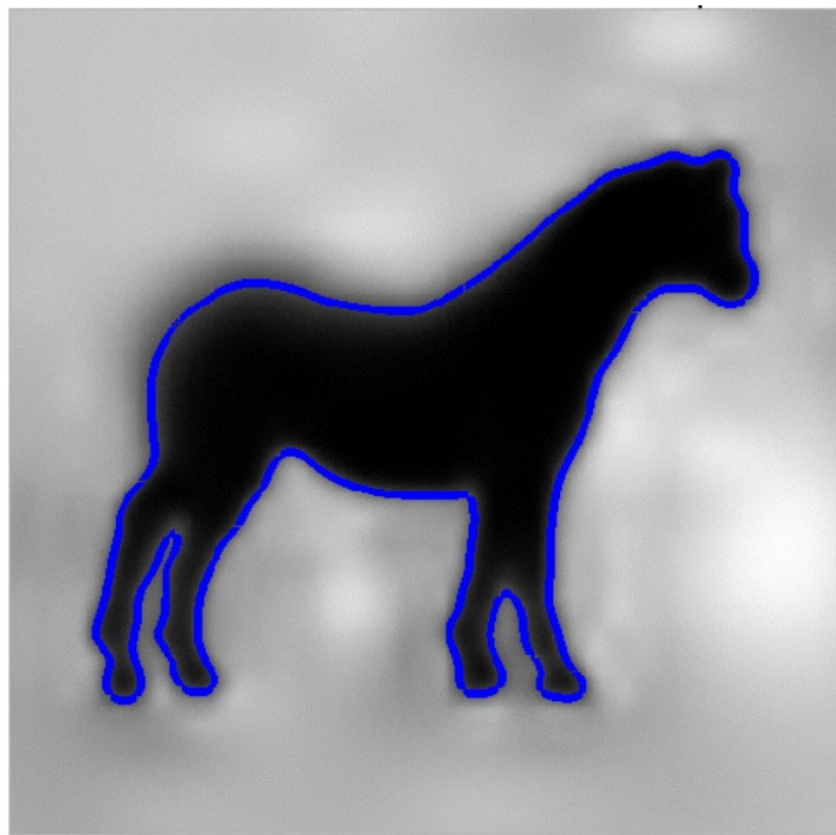
Differentiate,

Poisson  
equation

$$\Delta \chi = \nabla \cdot \vec{V}$$

# Process





# Results

