

Scan Conversion 1

(pages 72 -78 of textbook)

Scan Converting Lines

Line Drawing

- Draw a line on a raster screen between two points
- What's wrong with statement of problem?
 - doesn't say anything about which points are allowed as endpoints
 - doesn't give a clear meaning of "draw"
 - doesn't say what constitutes a "line" in raster world
 - doesn't say how to measure success of proposed algorithms

Problem Statement

- Given two points P and Q in XY plane, both with integer coordinates, determine which pixels on raster screen should be on in order to make picture of a unit-width line segment starting at P and ending at Q

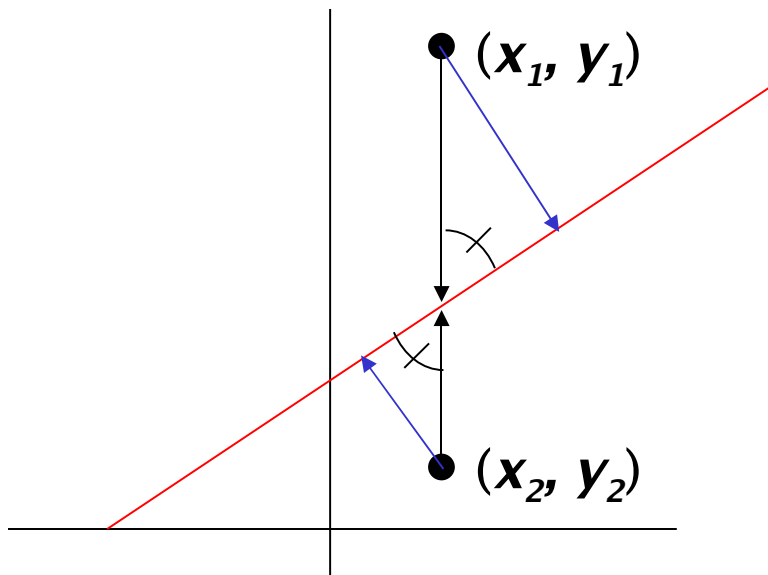
Finding next pixel:

Special case:

- Horizontal Line:
Draw pixel P and increment x coordinate value by 1 to get next pixel.
- Vertical Line:
Draw pixel P and increment y coordinate value by 1 to get next pixel.
- Diagonal Line:
Draw pixel P and increment both x and y coordinate by 1 to get next pixel.
- What should we do in general case?
 - Increment x coordinate by 1 and choose point closest to line.
 - But how do we measure “closest”?

Vertical Distance

- Why can we use vertical distance as measure of which point is closer?
 - because vertical distance is proportional to actual distance
 - how do we show this?
 - with similar triangles



- By similar triangles we can see that true distances to line (in blue) are directly proportional to vertical distances to line (in black) for each point
- Therefore, point with smaller vertical distance to line is closest to line

Strategy 1 – Incremental Algorithm (1/2)

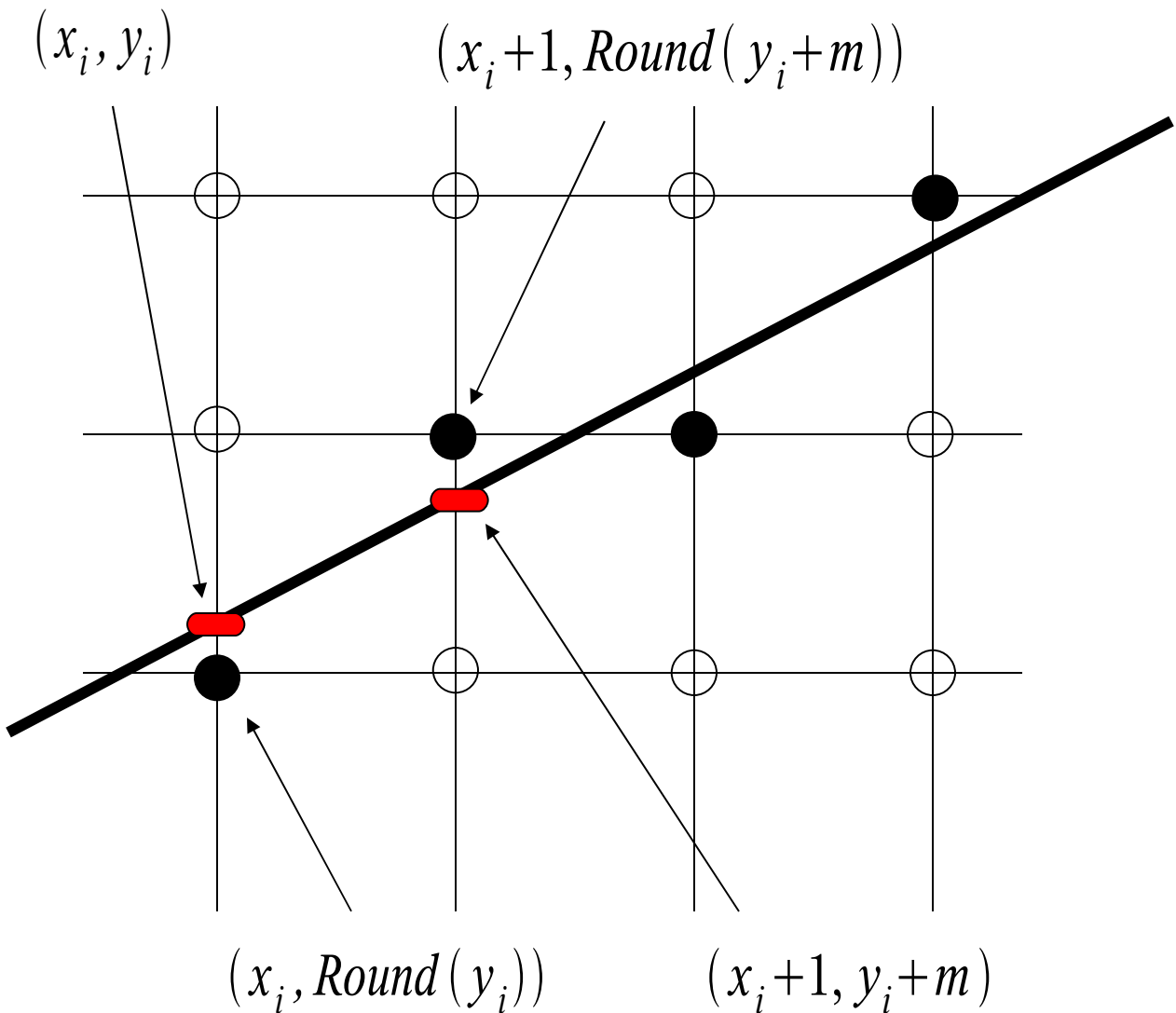
Basic Algorithm

- Find equation of line that connects two points P and Q
- Starting with leftmost point P , increment x_i by 1 to calculate $y_i = m * x_i + B$
where m = slope, B = y intercept
- Draw pixel at $(x_i, \text{Round}(y_i))$ where
 $\text{Round}(y_i) = \text{Floor}(0.5 + y_i)$

Incremental Algorithm:

- Each iteration requires a floating-point multiplication
 - Modify algorithm to use deltas
- If $\Delta x = 1$, then $y_{i+1} = y_i + m$
- At each step, we make incremental calculations based on preceding step to find next y value

Strategy 1 – Incremental Algorithm (2/2)



Example Code

```
// Incremental Line Algorithm
// Assume x0 < x1

void Line(int x0, int y0,
          int x1, int y1) {
    int x, y;
    float    dy = y1 - y0;
    float    dx = x1 - x0;
    float    m = dy / dx;

    y = y0;
    for (x = x0; x < x1; x++) {
        WritePixel(x, Round(y));
        y = y + m;
    }
}
```

Problem with Incremental Algorithm:

```
void Line(int x0, int y0,
          int x1, int y1) {
    int x, y;
    float    dy = y1 - y0;
    float    dx = x1 - x0;
    float    m = dy / dx;
```

```
    y = y0;
    for (x = x0; x < x1; x++) {
        WritePixel(x, Round(y));
        y = y + m;
    }
}
```

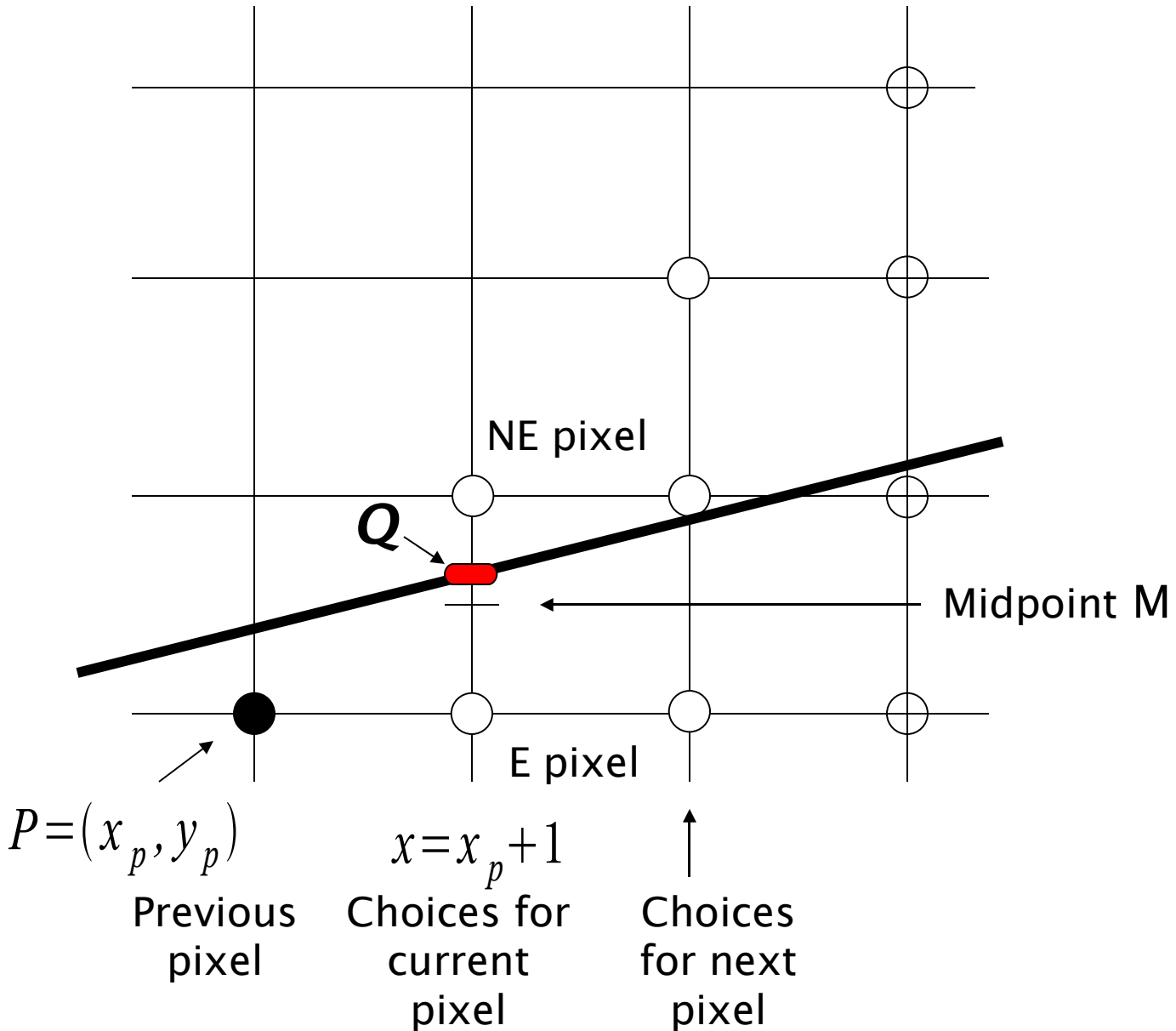
Rounding takes time

Since slope is fractional, need special case for vertical lines

Strategy 2 – Midpoint Line Algorithm (1/3)

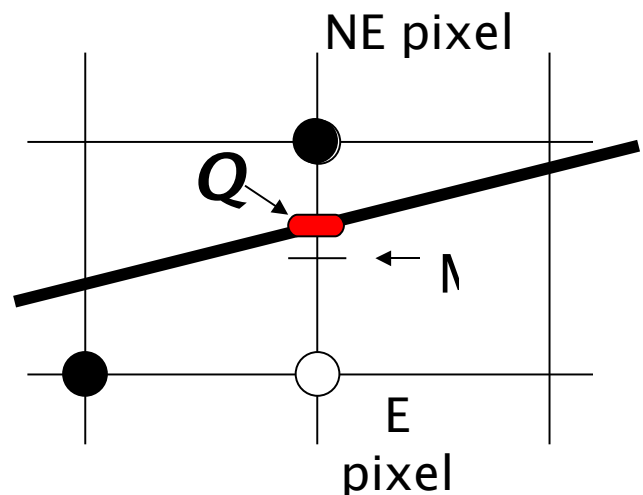
- Assume that line's slope is shallow and positive ($0 < \text{slope} < 1$); other slopes can be handled by suitable reflections about principle axes
- Call lower left endpoint (x_0, y_0) and upper right endpoint (x_1, y_1)
- Assume that we have just selected pixel P at (x_p, y_p)
- Next, we must choose between pixel to right (E pixel), or one right and one up (NE pixel)
- Let Q be intersection point of line being scan-converted and vertical line $x = x_p + 1$

Strategy 2 - Midpoint Line Algorithm (2/3)



Strategy 2 – Midpoint Line Algorithm (3/3)

- Line passes between E and NE
- Point that is closer to intersection point Q must be chosen
- Observe on which side of line midpoint M lies:
 - E is closer to line if midpoint M lies above line, i.e., line crosses bottom half
 - NE is closer to line if midpoint M lies below line, i.e., line crosses top half
- Error (vertical distance between chosen pixel and actual line) is always $\leq \frac{1}{2}$
- Algorithm chooses NE as next pixel for line shown
- Now, need to find a way to calculate on which side of line midpoint lies



Line

Line equation as function $f(x)$:

$$y = mx + B$$

$$y = \frac{dy}{dx} x + B$$

Line equation as implicit function:

$$f(x, y) = ax + by + c = 0$$

for coefficients a , b , c , where a , $b \neq 0$

from above,

$$y \cdot dx = dy \cdot x + B \cdot dx$$

$$dy \cdot x - y \cdot dx + B \cdot dx = 0$$

$$a = dy, b = -dx, c = B \cdot dx$$

Properties (proof by case analysis):

- $f(x_m, y_m) = 0$ when any point M is on line
- $f(x_m, y_m) < 0$ when any point M is above line
- $f(x_m, y_m) > 0$ when any point M is below line
- Our decision will be based on value of function at midpoint M at $(x_p + 1, y_p + \frac{1}{2})$

Decision Variable

Decision Variable d :

- We only need sign of $f(x_p + 1, y_p + \frac{1}{2})$ to see where line lies, and then pick nearest pixel
- $d = f(x_p + 1, y_p + \frac{1}{2})$
 - if $d > 0$ choose pixel NE
 - if $d < 0$ choose pixel E
 - if $d = 0$ choose either one consistently

How do we incrementally update d ?

- On basis of picking E or NE, figure out location of M for that pixel, and corresponding value of d for next grid line
- We can derive d for the next pixel based on our current decision

If E was chosen:

Increment M by one in x direction

$$\begin{aligned} d_{new} &= f(x_p + 2, y_p + \frac{1}{2}) \\ &= a(x_p + 2) + b(y_p + \frac{1}{2}) + c \end{aligned}$$

$$d_{old} = a(x_p + 1) + b(y_p + \frac{1}{2}) + c$$

- $d_{new} - d_{old}$ is the incremental difference ΔE

$$d_{new} = d_{old} + a$$

$$\Delta E = a = dy \text{ (2 slides back)}$$

- We can compute value of decision variable at next step incrementally without computing $F(M)$ directly

$$d_{new} = d_{old} + \Delta E = d_{old} + dy$$

- ∇ ΔE can be thought of as correction or update factor to take d_{old} to d_{new}

- It is referred to as forward difference

If NE was chosen:

Increment M by one in both *x* and *y* directions

$$\begin{aligned} d_{new} &= F(x_p + 2, y_p + 3/2) \\ &= a(x_p + 2) + b(y_p + 3/2) + c \end{aligned}$$

$$\forall \Delta NE = d_{new} - d_{old}$$

$$d_{new} = d_{old} + a + b$$

$$\Delta NE = a + b = dy - dx$$

- Thus, incrementally,

$$d_{new} = d_{old} + \Delta NE = d_{old} + dy - dx$$

Summary (1/2)

- At each step, algorithm chooses between 2 pixels based on sign of decision variable calculated in previous iteration.
- It then updates decision variable by adding either ΔE or ΔNE to old value depending on choice of pixel.
Simple additions only!
- First pixel is first endpoint (x_0, y_0) , so we can directly calculate initial value of d for choosing between E and NE.

Summary (2/2)

- First midpoint for first $d = d_{start}$ is at $(x_0 + 1, y_0 + \frac{1}{2})$
- $f(x_0 + 1, y_0 + \frac{1}{2})$

$$= a(x_0 + 1) + b(y_0 + \frac{1}{2}) + c$$

$$= a * x_0 + b * y_0 + c + a + b/2$$

$$= f(x_0, y_0) + a + b/2$$
- But (x_0, y_0) is point on line and $f(x_0, y_0) = 0$
- Therefore, $d_{start} = a + b/2 = dy - dx/2$
 - use d_{start} to choose second pixel, etc.
- To eliminate fraction in d_{start} :
 - redefine f by multiplying it by 2; $f(x,y) = 2(ax + by + c)$
 - this multiplies each constant and decision variable by 2, but does not change sign
- Bresenham's line algorithm is same but doesn't generalize as nicely to circles and ellipses

Example Code

```
void MidpointLine(int x0, int y0,
                 int x1, int y1) {
    int dx = x1 - x0;
    int dy = y1 - y0;
    int d = 2 * dy - dx;
    int incrE = 2 * dy;
    int incrNE = 2 * (dy - dx);
    int x = x0;
    int y = y0;

    writePixel(x, y);

    while (x < x1) {
        if (d <= 0) { // East Case
            d = d + incrE;
        } else { // Northeast Case
            d = d + incrNE;
            y++;
        }
        x++;
        writePixel(x, y);
    } // while */
} // MidpointLine */
```