Collision Detection for Complex Environments
What is Collision Detection

Finding coincident geometry

- e.g. what polygons intersect in this environment

Detection by object

- Don’t care about collisions among an object’s polygons
- Choice of “what is an object” somewhat arbitrary
Applications

Motion planning
• Compute collision-free paths for automated tasks

Virtual prototyping / simulation
• Test functionality of mechanical assemblies

Computer animation
• Physically-based animations

Virtual environments
• Detect interactions of user with environment
• Determine interactions among virtual objects
Triangle-Triangle Intersection

Intersect if edge of one triangle intersects other triangle

- 6 such tests produces complete tri-tri test
- Faster methods possible

Edge-triangle intersection

- Find intersection of line and plane
- Check if intersection is within edge
- Check if intersection is within triangle
Bounding volume hierarchies

- Spheres, axis-aligned bounding boxes, oriented bounding boxes
  - simple volume have faster tests, but may require more tests than complex volumes (even asymptotically more)

- Construct hierarchy for each object

- Prune out unnecessary collision tests
  - if two bounding volumes do not collide, their children do not collide
Bounding Volume Examples

- Sphere
- Axis-Aligned Bounding Box
- Oriented Bounding Box
- General Slab Intersection
Bounding Volume Hierarchy

Example
Bounding Volume Hierarchy
Computing Hierarchies

Top-down

Bottom-up

Minimize volume/surface area

Computing “good” hierarchies is difficult
Indicate order of traversing a pair of bounding volume hierarchies

Not generally represented explicitly
Cost of Proximity Queries

\[ T = N_{bv} \times C_{bv} + N_{p} \times C_{p} \]

- Top-down method of OBB tree construction
- Fast OBB-OBB overlap test with separating axis theorem
- OBB trees asymptotically faster than sphere or AABB trees for parallel close proximity
N-body Collision Detection

Given n moving objects and m stationary objects, find all pairs of intersecting objects.
Goals

Speed

• want algorithm to be output sensitive, something like $O(n+s)$

Accuracy

• accuracy to the precision of the models

Assumptions

• temporal coherence

• no assumptions about accelerations or velocities of objects, except that sampling rate is high enough to detect collisions
Worst Case Complexity

Assuming none of the stationary objects are intersecting each other (or we are not concerned with these intersections), worst case output size:

\[ s = O(n^2 + nm) \]
Space Partitioning Approaches

Partition space into small units.

Only test for collisions between objects in each of these units.

Examples

• Uniform Spatial Subdivision
• Octrees
• K-d trees, R-trees, etc.
Uniform Spacial Subdivision

Partition space into a large number of boxes.

Decide which boxes each object falls into.

Only test for collisions between pairs of objects in each box.

Very simple.

Very memory intensive.

Difficult/impossible to choose proper box size.
Octree

Start with all of space in a single cube.

Recursively subdivide cube into 8 equal sub-cubes until either the cube contains fewer than a set number of objects or the level of recursion reaches some maximum.
Octree (cont.)

Cell size adapts to arrangement of objects in the environment.

Memory used more efficiently than uniform spacial subdivision, but may still be wasteful.

Still difficult to choose cutoff sizes.
Object Sorting

Sort objects in space to determine which object pairs overlap.

Test only these pairs for collisions.

(methods for determining overlaps and testing collisions are often independent).
Dimension Reduction

• project bounding boxes of objects onto planes or lines

• “sort” in lower-dimensional space

• determine overlaps in lower-dimensional space

• overlap in all lower-dimensional spaces indicates overlap in the higher dimensional space
Dimension Reduction (2D)

Before

A

B

C

After

A

B

C

Box A moves to overlap box B
Bounding Boxes

Conservatively-sized cubes

• Shape invariant for object rotations

Arbitrary AABBs for tighter fit

• Update incrementally as objects rotate
Convex objects
  • Use local walk to update extremal vertices

Non-convex objects
  • Precompute convex hull or other tight, convex bounding volume
  • Apply incremental walk to bounding volume
List Sorting

- Use temporal coherence
- Typically sort in $O(n)$ time
- Each swap toggles a 1D overlap status

Advantage - simple and efficient

Disadvantage - many swaps/overlaps in 1D
Range Queries in 2D and 3D

Interval/Segment Trees

- $O(n \log n)$ to construct
- Each query $O(\log n)$
- Inserting/Deleting a range $O(\log n)$

Advantage - fewer overlaps in higher dimensions

Disadvantage - more complex structures, with larger overhead (constant factors matter)
I-Collide

Collision detection for convex polyhedra

- Tracks pair-wise closest distances
- Reports distance and collisions
- Performs exact collision tests
- Sub-linear in terms of object complexity
- Output sensitive in terms of number of objects
- Fast in practice
System Architecture

- Object transformations
- N-body Prune
- Overlapping pairs
- Colliding pairs
- Exact Collision Detection
- Application
Multi-body simulation

1000 moving polyhedra

Runs at over 15 frames per second on Onyx RE R4400
I_COLLIDE Results

Fairly linear with respect to number of objects and object/volume density

N-body simulation with 500 objects runs at about 30 frames/sec (without graphics).
Collision detection for large polygonal environments

- Combines I-Collide pruning algorithm with RAPID intersection test
- Provides efficient collision detection for n arbitrary polygonal models
- Improves space efficiency over I-Collide implementation
Multi-bunny Simulation