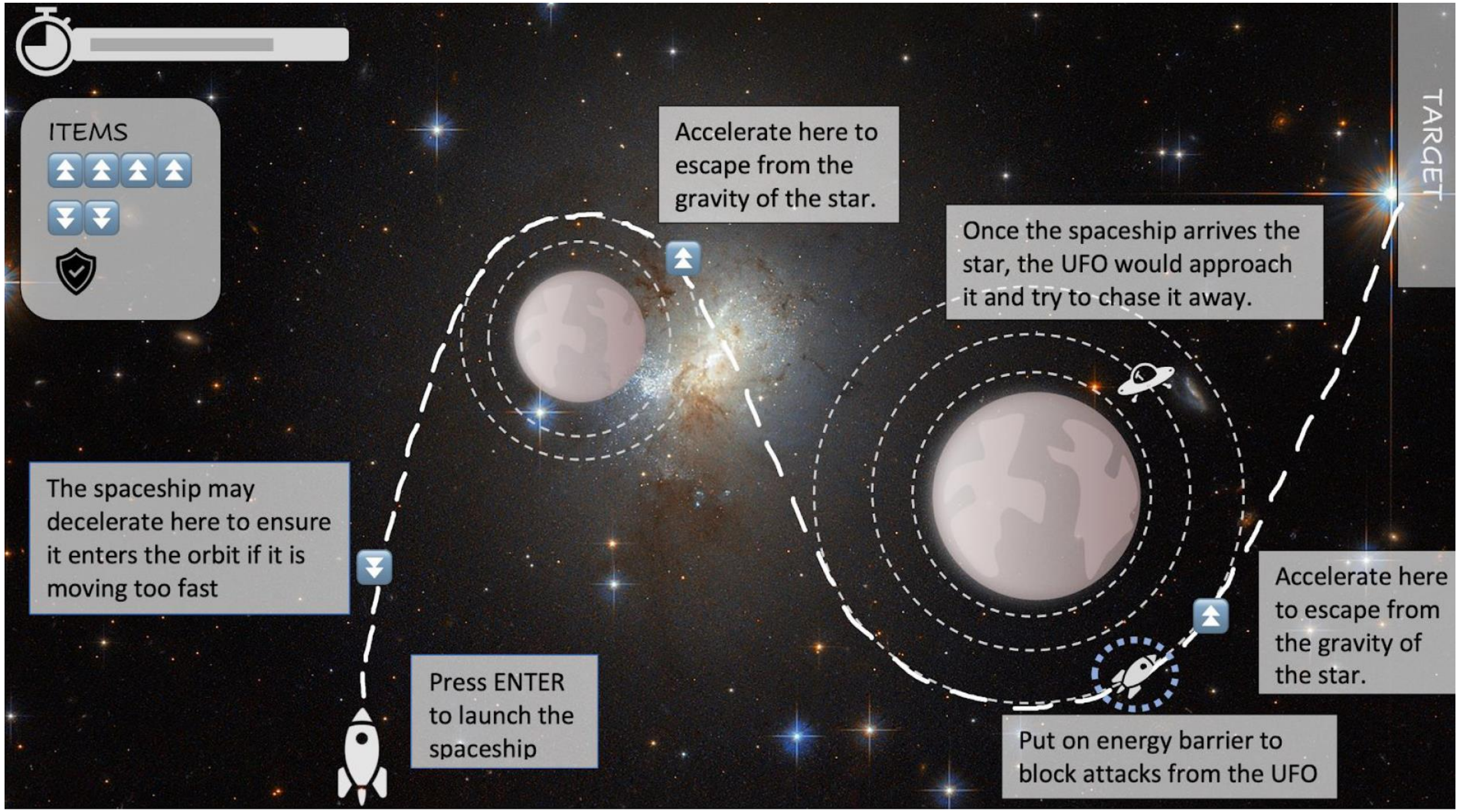
Helge Rhodin

CPSC 427
Video Game Programming

Physical Simulation



Setup

@Helge: Pressed record?

@Class: Logged into iClicker cloud?

Logistics: Exam slot?

- ***Final cross-play session***
- ***Industry jury***
- ***Awards***
- ***Attendance mandatory***

- ***Sheduled: Dec 18th, noon***

- ***Better on Dec 17th 4-6 pm? -> vote on piazza, particularly if you can't make it***

Logistics: M2 submission and A2 grading

- ***On Friday***

- ***30 students selected for face2face grading (on zoom)***

- Please check if you are selected and register for a slot
  - *First come first served*
  - *https://docs.google.com/spreadsheets/d/1hWECo-Y2Xaz9oHybqjr4xZGnLMqCRW7JrZYzarcSerg/edit?usp=sharing*

Logistics: Guest lecture

By Ralf Karrenberg

- ***Nvidia***
- ***Raytracing (RTX technology) and upscaling (DLSS)***
  - *How light simulation and AI/ML play together*

Overview

1. Equation of Motion

- Examples
- Ordinary Differentiable Equations (ODE)
- Solving ODEs

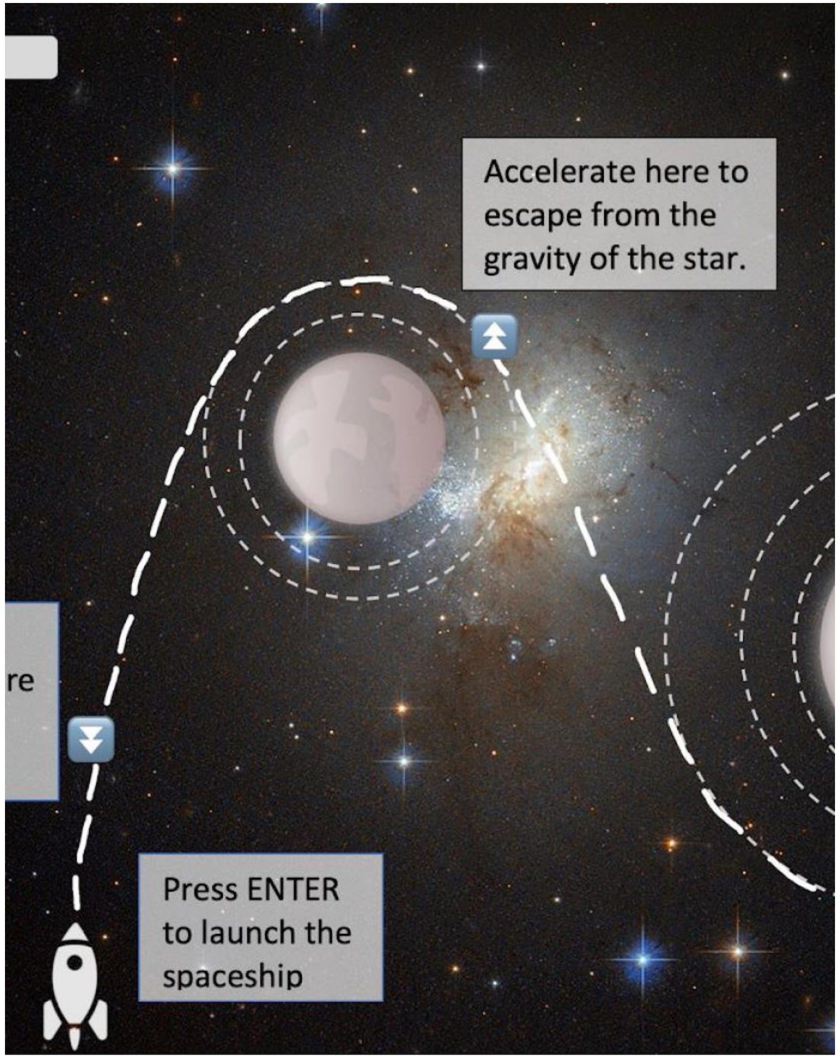
2. Collision and Reaction Forces

Physics

Learning goals:

- ***Connect your theoretical math knowledge to applications***

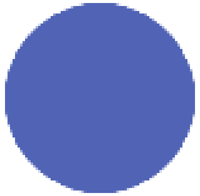
- ***Properly simulate object motion and their interaction in your game***



Recap: Basic Particle Simulation (first try)

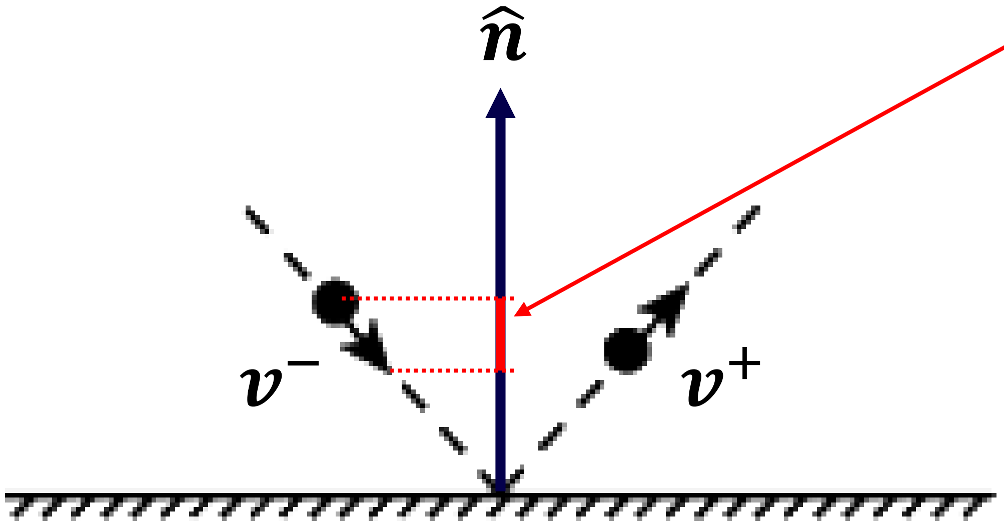
How to compute the change in velocity?

$$d_t = t_{i+1} - t_i$$
$$\vec{v}_{i+1} = \vec{v}_i + \Delta v$$
$$\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}_i d_t$$



Recap: Particle-Plane Collision

- ***In direction of normal***



Velocity along normal
(v projected on normal
by the dot product)

Frictionless

$$\Delta v = 2(v^- \circ \hat{n})\hat{n}$$

Apply change
along normal
(magnitude
times direction)

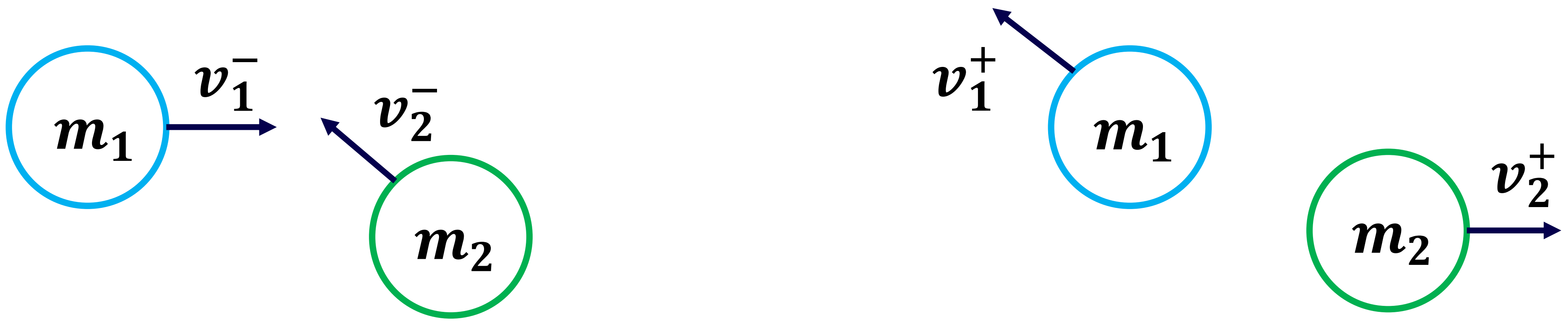
$$v^+ = v^- + \Delta v$$

Loss of energy

$$\Delta v = (1 + \epsilon)(v^- \circ \hat{n})\hat{n}$$

Particle-Particle Collisions (spherical objects)

Before collision **After**



Response:

$$v_1^+ = v_1^- - \frac{2m_2}{m_1+m_2}\frac{\langle v_1^- - v_2^-\rangle \cdot \langle p_1 - p_2\rangle}{\|p_1 - p_2\|^2}\langle p_1 - p_2\rangle$$

$$v_2^+ = v_2^- - \frac{2m_1}{m_1+m_2}\frac{\langle v_2^- - v_1^-\rangle \cdot \langle p_2 - p_1\rangle}{\|p_2 - p_1\|^2}\langle p_2 - p_1\rangle$$

- This is in terms of velocity
- Today (and next lecture): derivation via impulse and forces

From Velocities (Δv) to Forces (F) and back

Force relates to mass and acceleration

$$\mathbf{F} = ma$$

A change in velocity related to acceleration over time

$$\Delta \mathbf{v} = \Delta t \, a$$

In terms of forces

$$\Delta \mathbf{v} = \Delta t \, \frac{F}{m}$$

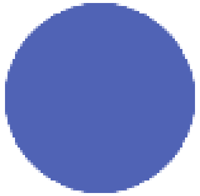
Recap: Basic Particle Simulation (first try)

How to compute the change in velocity?

$$d_t = t_{i+1} - t_i$$

$$\vec{v}_{i+1} = \vec{v}_i + \Delta v$$

$$\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}_i d_t$$



Forces are omnipresent

- **Gravity**

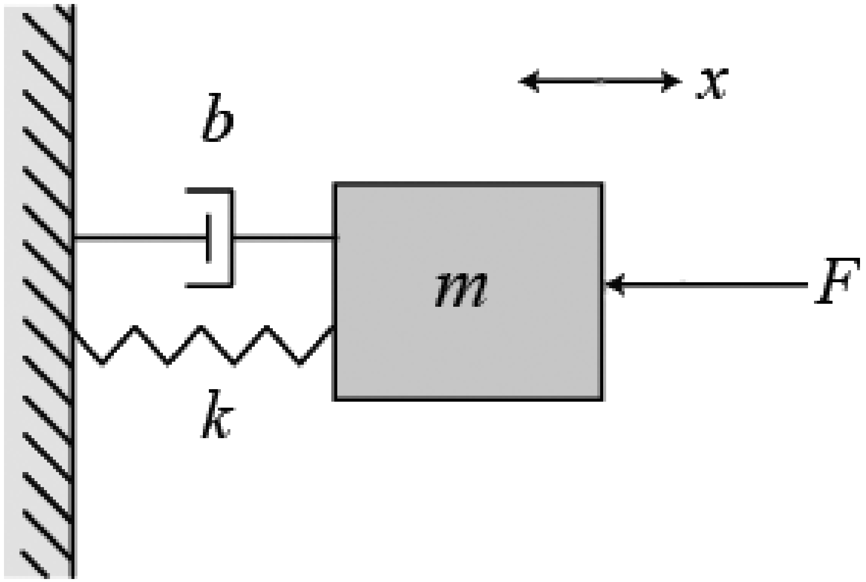
$$F = \begin{bmatrix} 0 \\ -mg \end{bmatrix}$$

- **Viscous damping**

$$F = -bv$$

- **Spring & dampers**

$$F = -kx - bv$$



Gravity direction?

Assuming a flat earth:

$$F = \begin{bmatrix} 0 \\ -mg \end{bmatrix}$$

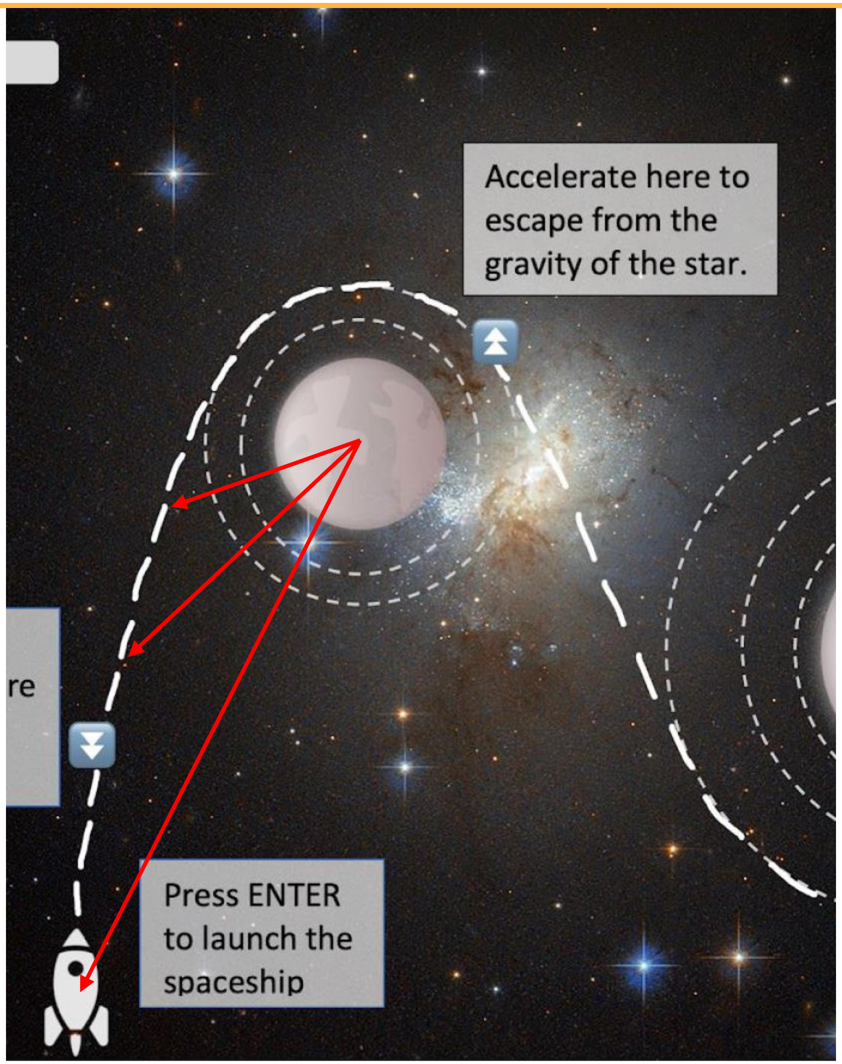
Assuming a spherical earth:

$$F = -mg \begin{bmatrix} a \\ b \end{bmatrix}$$

How to compute the vector (a,b) and g ?

Newton's law of universal gravitation

$$F = G\frac{m_1 m_2}{r^2}$$



Multiple forces?

Forces add up (and cancel):

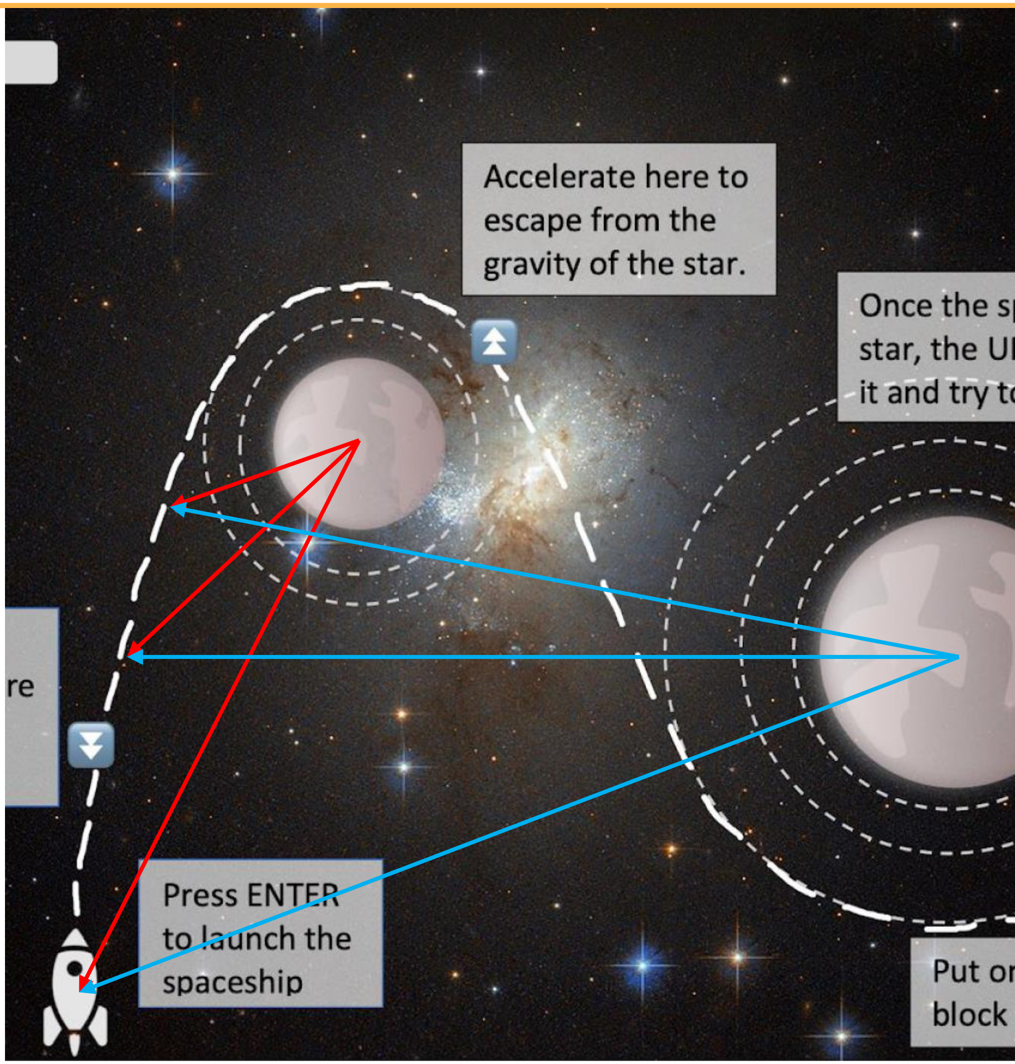
$$F = -m g_1 \begin{bmatrix} a_1 \\ b_1 \end{bmatrix} - m g_2 \begin{bmatrix} a_2 \\ b_2 \end{bmatrix}$$

- ***This holds for all types of forces!***

- ***Notation you might see:***

$$F = \textstyle\sum_i F_i = \sum F_i = \sum F$$

$$\vec{F} = F$$



Your game idea does not need forces?

Are you sure?

- ***Particle effects***
- ***Fake forces***
- ***Proxy forces***
  - Simulate crowd behaviour

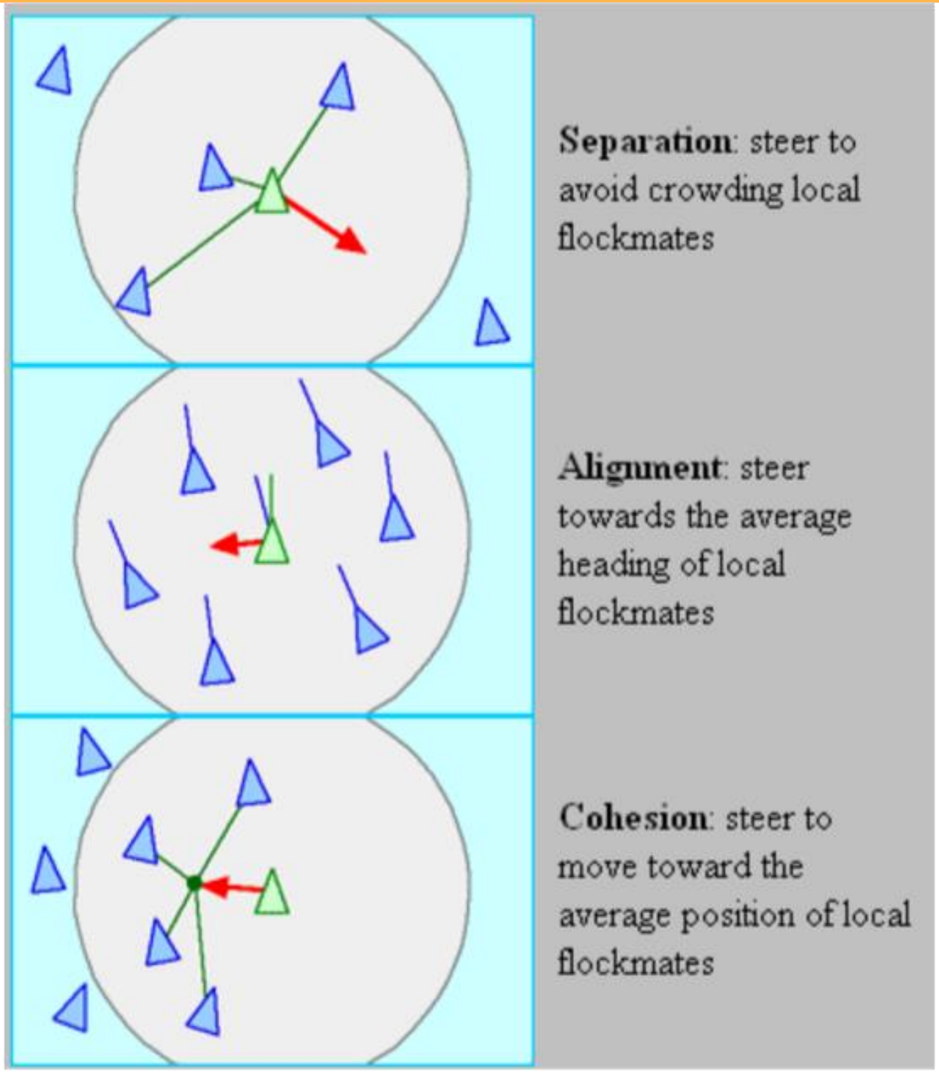
Take it as a chance to connect dry math with a practical application!

Proxy Forces (= fake forces)

- **Behavior forces: [“Boids”, Craig Reynolds, SIGGRAPH 1987]**
- **flocking birds, schooling fish, etc.**

- **Attract to goal location (like gravity)**
  - ***E.g., waypoint determined by shortest path search***
- **Repulsion if close**
- **Align orientation to neighbors**
- **Center to neighbors**

- **Forces add up!**



Simulation Basics

Simulation loop…

1. ***Equations of Motion***
   - sum forces & torques
   - solve for accelerations: $\vec{\boldsymbol{F}} = \boldsymbol{ma}$
2. ***Numerical integration***
   - update positions, velocities
3. ***Collision detection***
4. ***Collision resolution***

What we did so far: Forward Euler

Forces only $\vec{F} = ma$

$$d_t = t_{i+1} - t_i$$
$$\vec{v}_{i+1} = \vec{v}_i + (\vec{F}(t_i)/m)d_t$$
$$\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}_{i+1}d_t$$

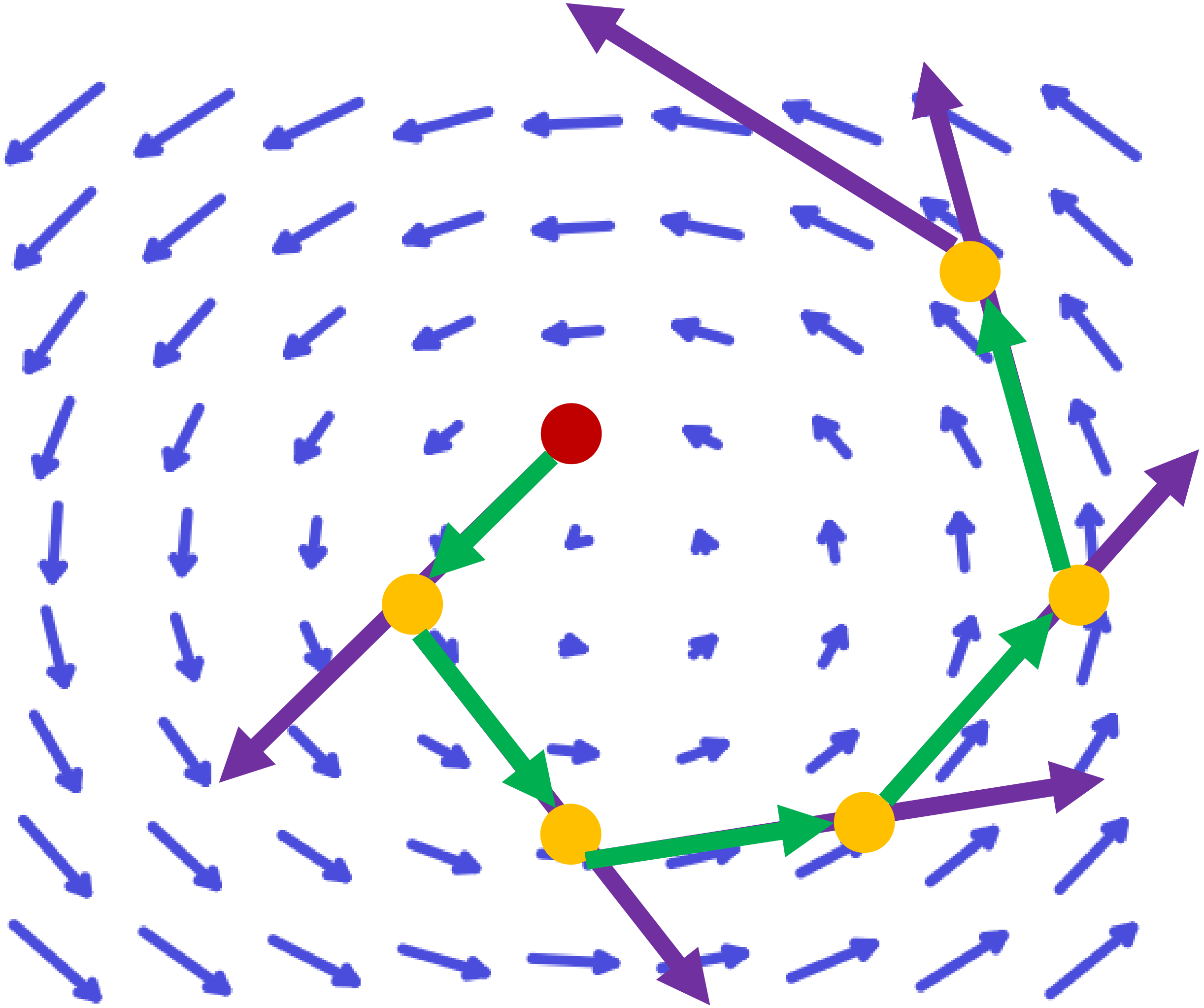
acceleration $= \frac{\partial v}{\partial t}$

get values at time t_{i+1} from values at time t_i

Issues? Alternatives?

How can we discretize this?

Issue: extrapolation

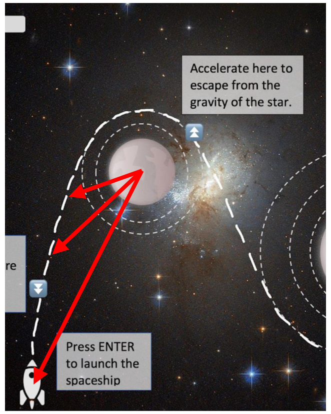


Which forces depend on t?

- **Gravity**

$$F = \begin{bmatrix} 0 \\ -mg \end{bmatrix}$$

$$F = -mg \begin{bmatrix} a \\ b \end{bmatrix}$$

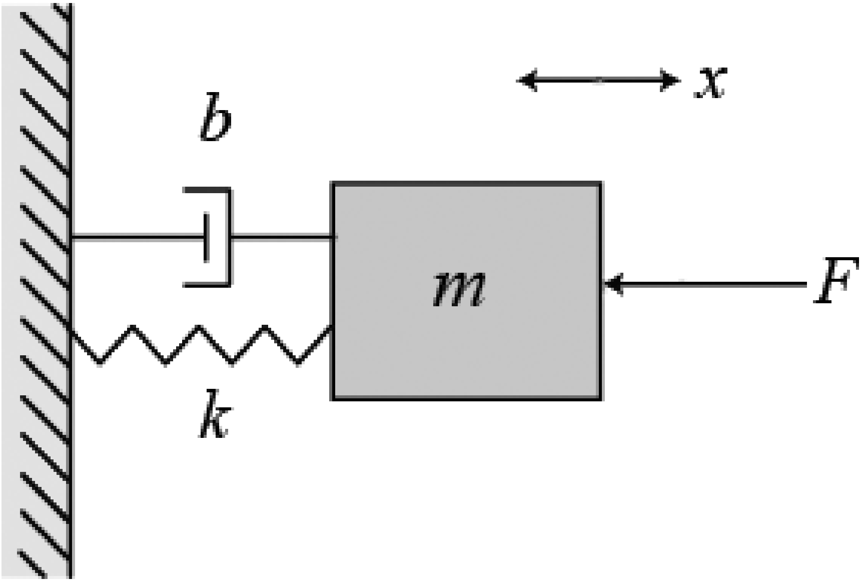


- **Viscous damping**

$$F = -bv$$

- **Spring & dampers**

$$F = -kx - bv$$



Basic Particle Simulation: Small Problem…

$$\boldsymbol{d_t = t_{i+1} - t_i}$$

$$\boldsymbol{\vec{v}_{i+1} = \vec{v}_i + (\vec{F}(t_{???})/m)d_t}$$

$$\boldsymbol{\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}_{i+1}d_t}$$

Equations of motion describe state (equilibrium)

- **Involves quantities and their derivatives**
  - **-> we need to solve differential equations**

Lets start from scratch

Given:

$$\vec{F} = m\,\frac{\partial^2 x}{\partial t^2}$$

Wait!

There is no position x in this equation?!

Only contains acceleration a!

How to solve such differential equation?

Desired: the position x at time t

$$x$$

Newtonian Physics as First-Order Diff. Eq. (DE)

Second-order DE

$$\vec{F} = m \frac{\partial^2 x}{\partial t^2}$$

acceleration

$= \frac{\partial v}{\partial t}$

First-order DE

$$\frac{\partial}{\partial t}\begin{bmatrix}\vec{x}\\ \vec{v}\end{bmatrix} = \begin{bmatrix}\vec{v}\\ \vec{F}/m\end{bmatrix}$$

velocity

$= \frac{\partial x}{\partial t}$

Now we have an x!

Higher-order DEs can be turned into a first-order DE with additional variables and equations!

Newtonian Physics as First-Order DE

- Motion of **one** particle

Second-order DE

$$\vec{F} = m \frac{\partial^2 x}{\partial t^2}$$

First-order DE

$$\frac{\partial}{\partial t}\begin{bmatrix} \vec{x} \\ \vec{v} \end{bmatrix} = \begin{bmatrix} \vec{v} \\ \Sigma\vec{F}/m \end{bmatrix}$$

- Motion of **many** particles

$$\frac{\partial}{\partial t}\begin{bmatrix} \overrightarrow{x_1} \\ \overrightarrow{v_1} \\ \overrightarrow{x_2} \\ \overrightarrow{v_2} \\ \vdots \\ \overrightarrow{x_n} \\ \overrightarrow{v_n} \end{bmatrix} = \begin{bmatrix} \overrightarrow{v_1} \\ \overrightarrow{F_1}/m_1 \\ \overrightarrow{v_2} \\ \overrightarrow{F_2}/m_2 \\ \vdots \\ \overrightarrow{v_n} \\ \overrightarrow{F_n}/m_n \end{bmatrix}$$

Overview

Different DE solvers

- ***Forward Euler***
  (take current accel. to update vel., current vel. to update pos.)

- ***Midpoint Method & Trapezoid Method***
  (mix current and approximations of future vel. & acc. Estimates)

- ***Backwards Euler***
  (solve for future pos., vel., and accel. jointly)
  - *May require an iterative solver*

Recap: Forward Euler

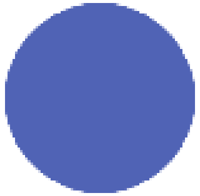
Forces only $\vec{F} = ma$

acceleration $= \frac{\partial v}{\partial t}$

$$d_t = t_{i+1} - t_i$$
$$\vec{v}_{i+1} = \vec{v}_i + (\vec{F}(t_i)/m)d_t$$
$$\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}_{i+1}d_t$$

get values at time t_{i+1} from values at time t_i

Issues? Alternatives?



Idea: Backwards Euler

- **Viscous damping**

  $F = -bv$

- **Spring & dampers**

  $F = -kx - bv$

$$\boldsymbol{d_t = t_{i+1} - t_i}$$

$$\boldsymbol{\vec{v}_{i+1} = \vec{v}_i + (\vec{F}(t_{i+1})/m)d_t}$$

$$\boldsymbol{\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}_{i+1}d_t}$$

get values at time t_{i+1} from states at time t_i and forces at t_{i+1}

Issues?

Differential Equations

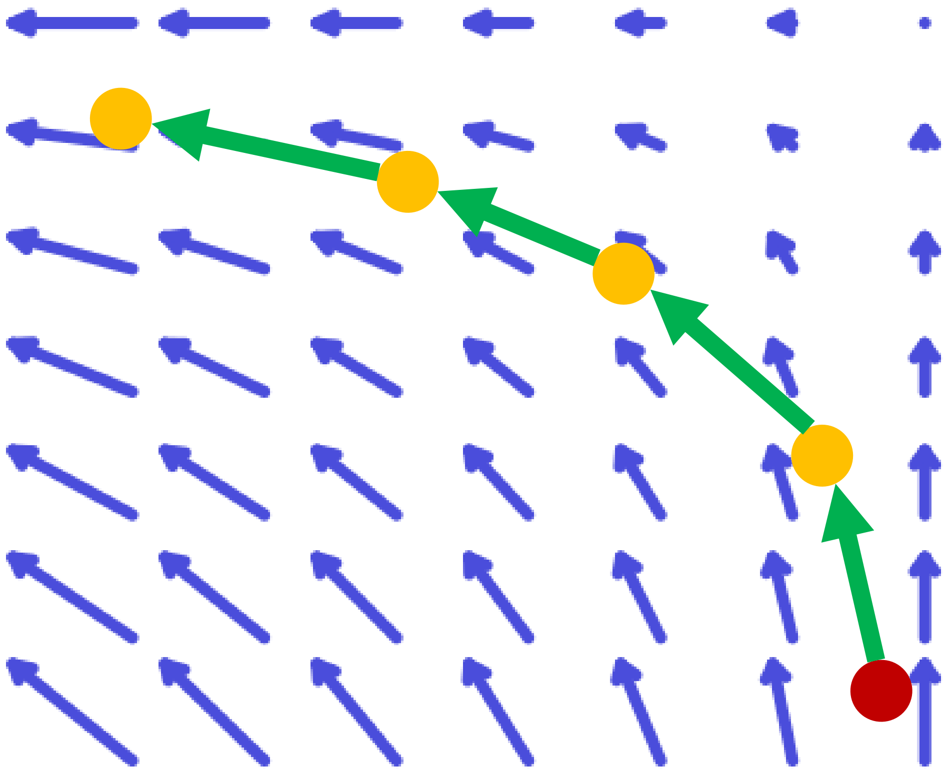
$$\frac{\partial}{\partial t}\vec{X}(t) = f(\vec{X}(t), t)$$

Given that $\vec{X}_0 = \vec{X}(t_0)$

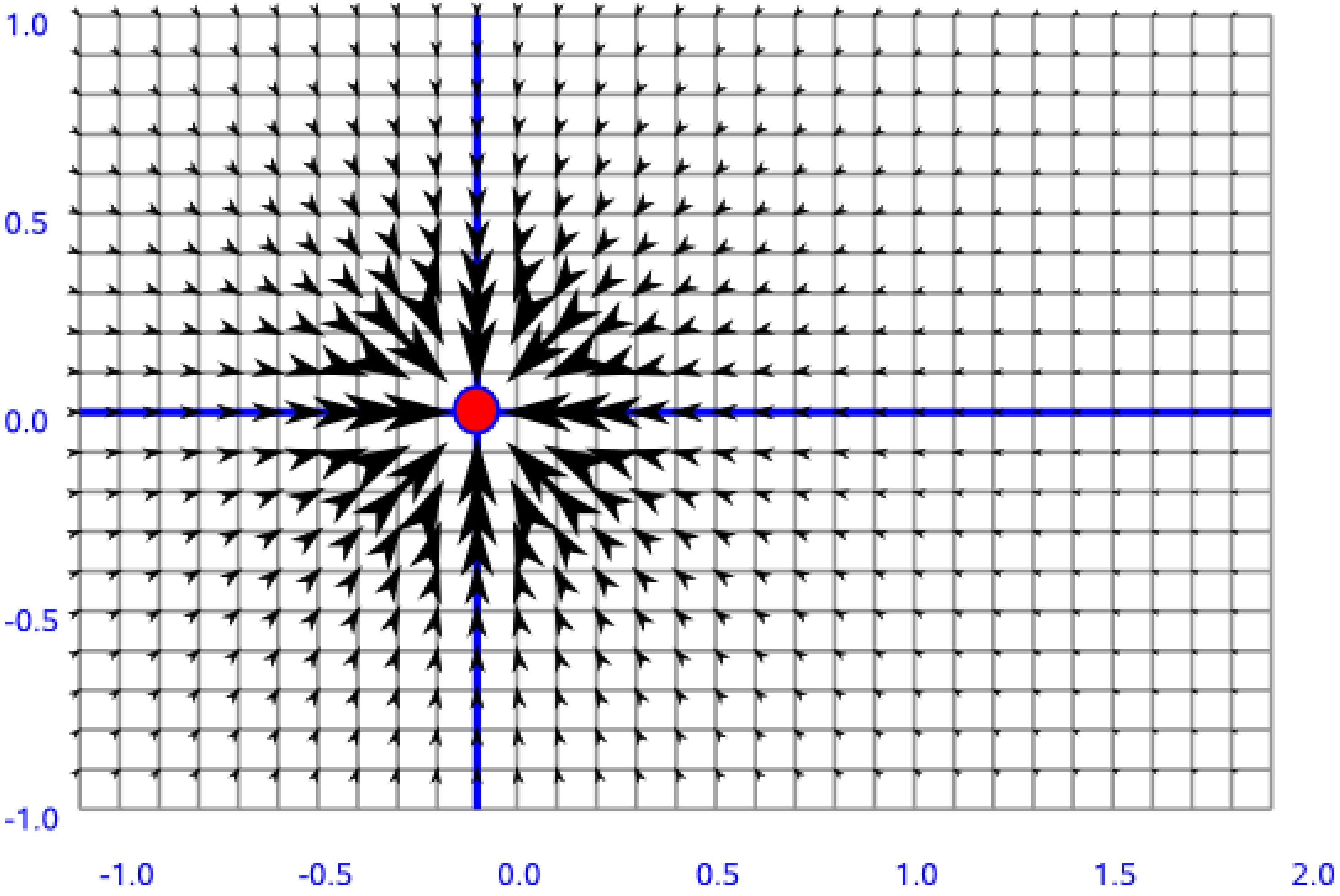
Compute $\vec{X}(t)$ **for** $\mathrm{t} > t_0$

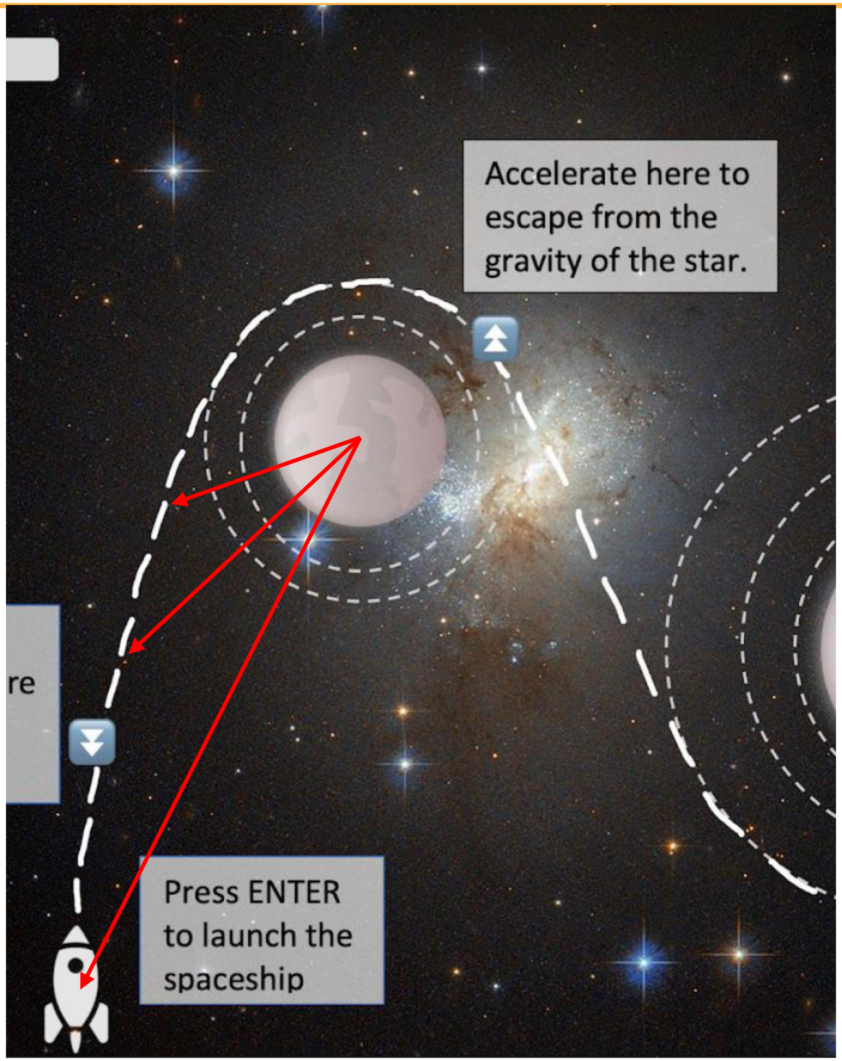
$$\Delta\vec{X}(t) = f(\vec{X}(t), t)\Delta t$$

- **Simulation:**
  - ***path through state-space***
  - ***driven by vector field***



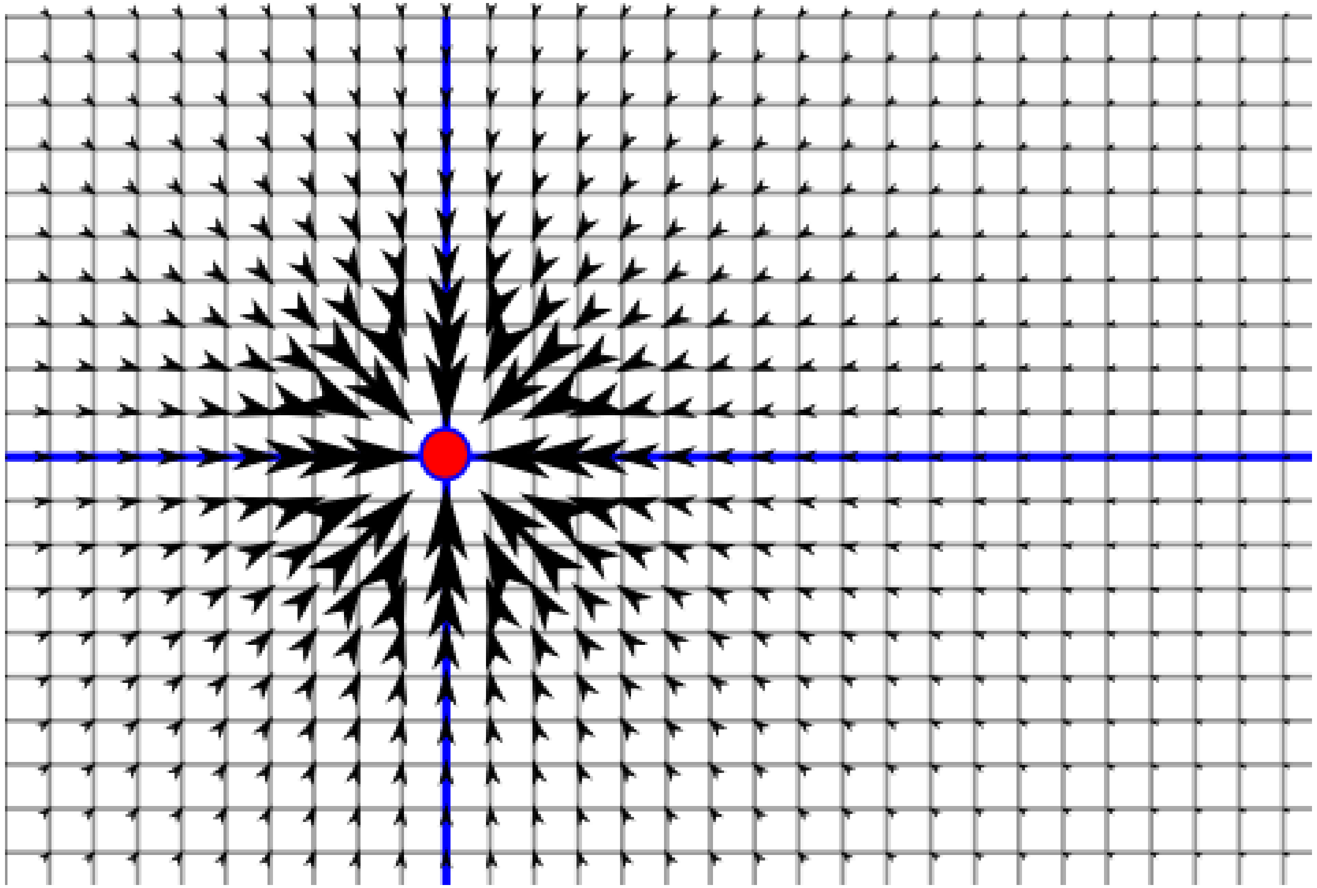
Gravitational field





https://www.euclideanspace.com/maths/geometry/space/fields/index.htm

Water Vortex (assignment?)



DE Numerical Integration: Explicit (Forward) Euler

$$\frac{\partial}{\partial t}\vec{X}(t) = f(\vec{X}(t), t)$$

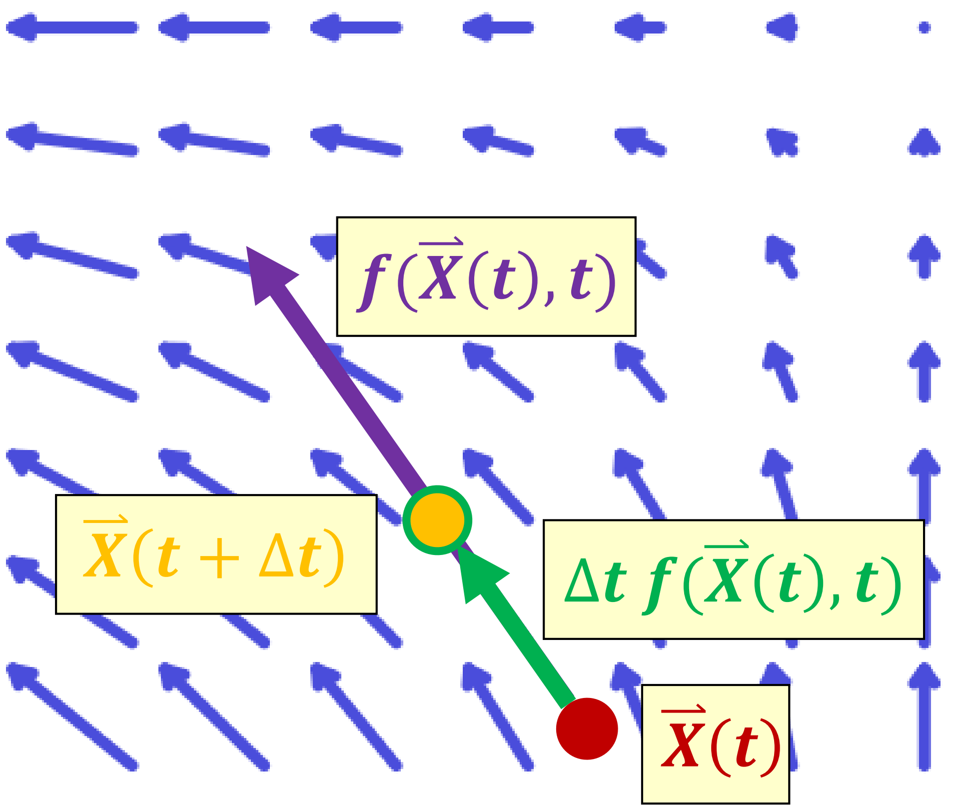
Given that $\vec{X}_0 = \vec{X}(t_0)$

Compute $\vec{X}(t)$ **for** $\mathrm{t} > \mathrm{t}_0$

$$\Delta t = \mathrm{t}_i - \mathrm{t}_{i-1}$$

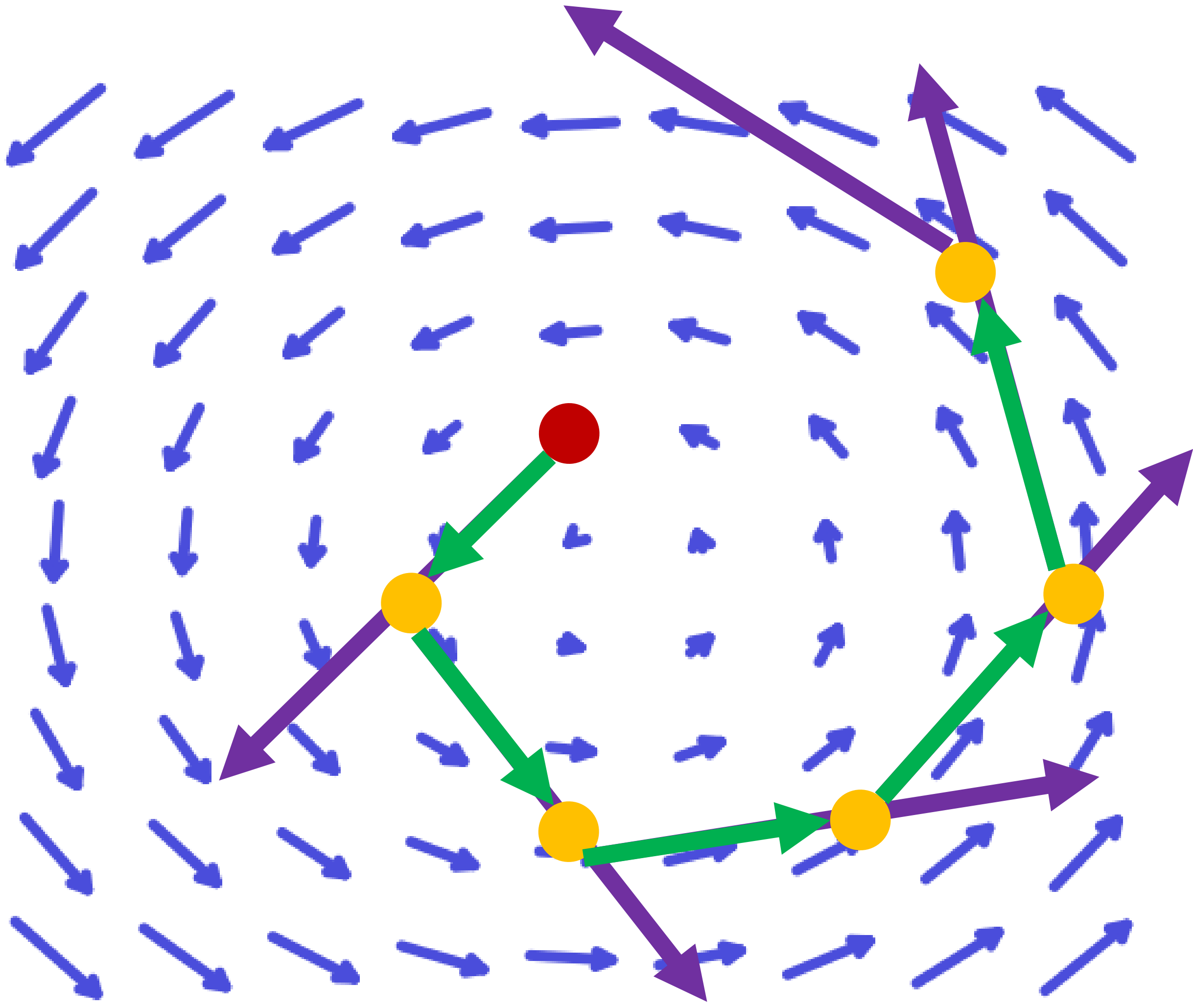
$$\Delta\vec{X}(\mathrm{t}_{i-1}) = \Delta t\, f(\vec{X}(\mathrm{t}_{i-1}), \mathrm{t}_{i-1})$$

$$\vec{X}_i = \vec{X}_{i-1} + \Delta t\, f(\vec{X}_{i-1}, \mathrm{t}_{i-1})$$



Explicit Euler Problems

- Solution spirals out
  - *Even with small time steps*
  - *Although smaller time steps are still better*

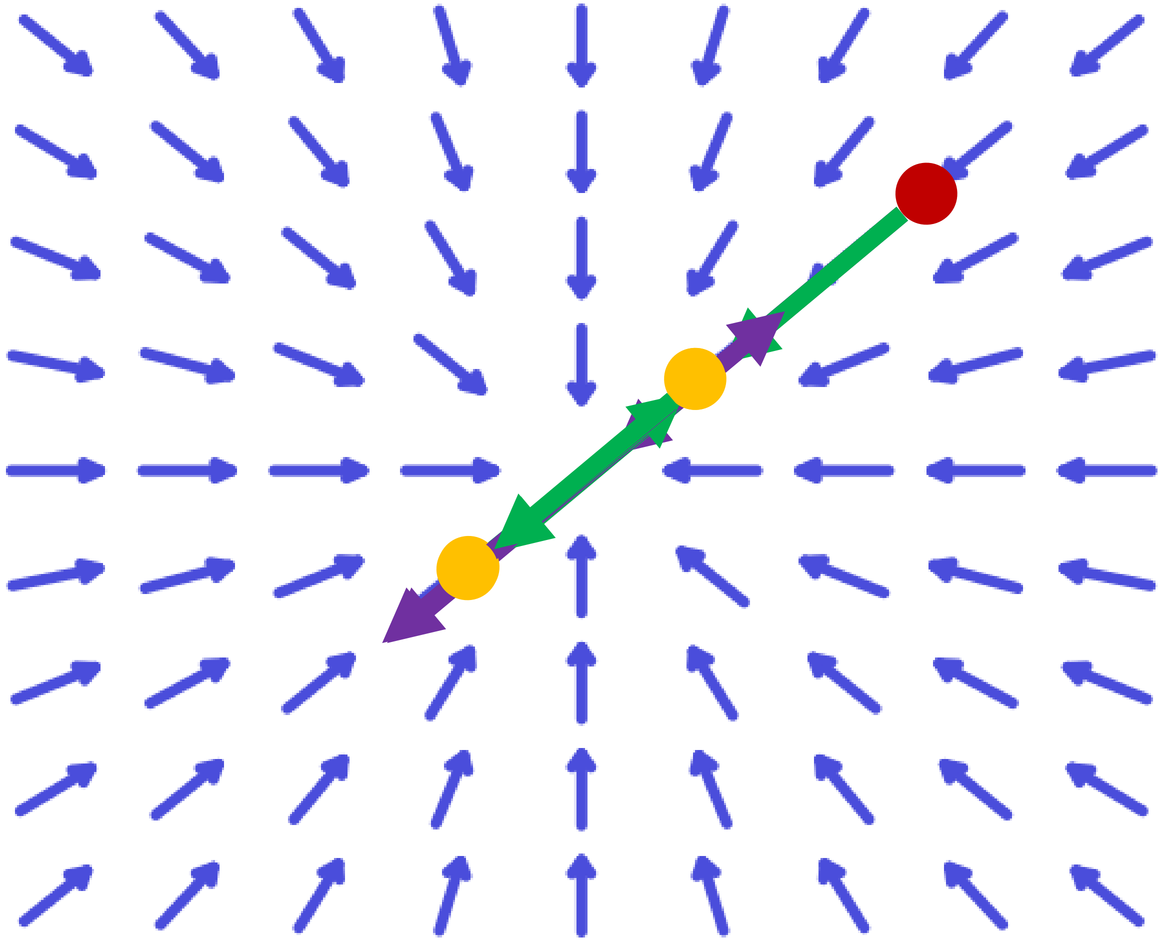


Definition: Explicit

- ***Closed-form/analytic solution***
- **no iterative solve required**

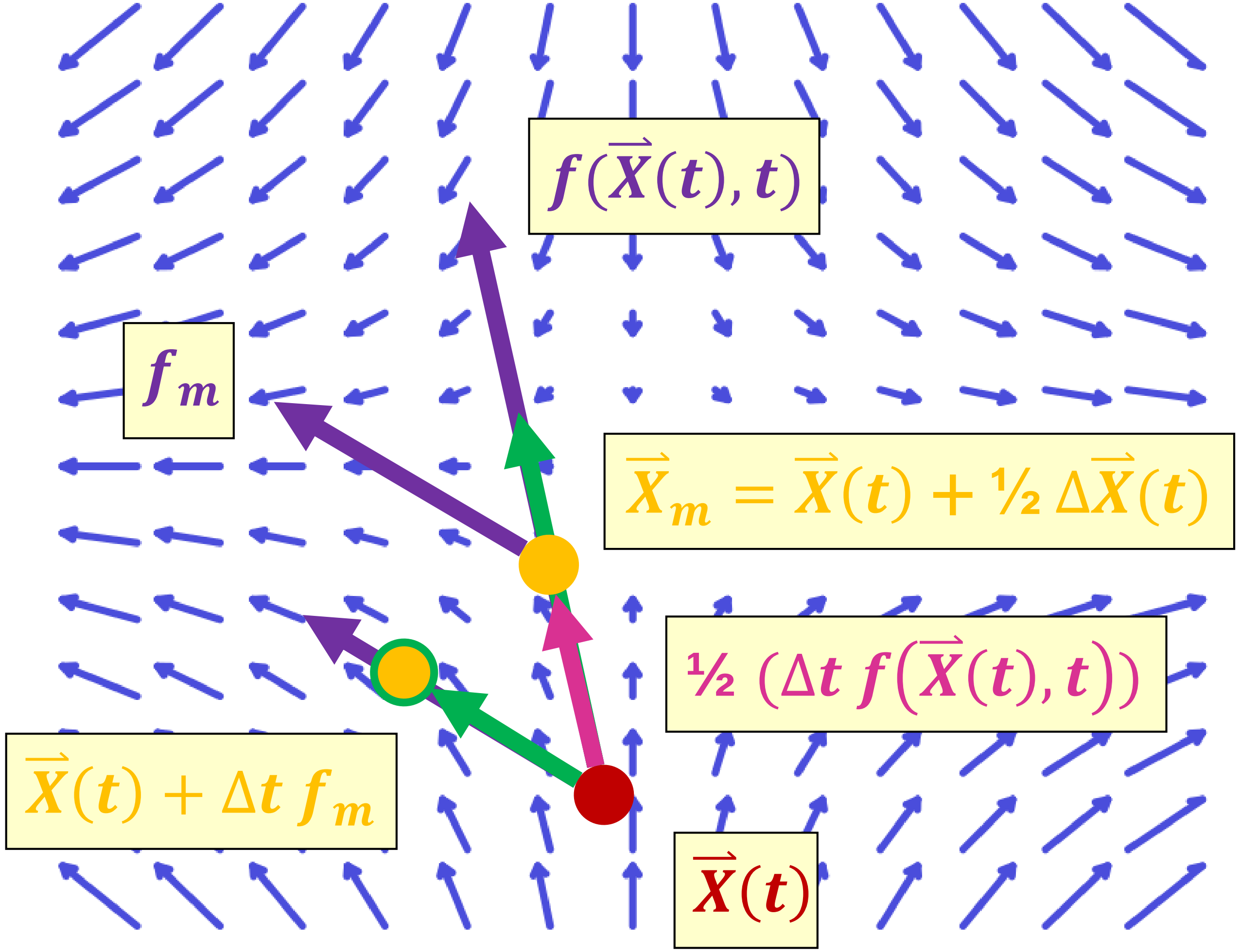
Explicit Euler Problems

- Can lead to instabilities



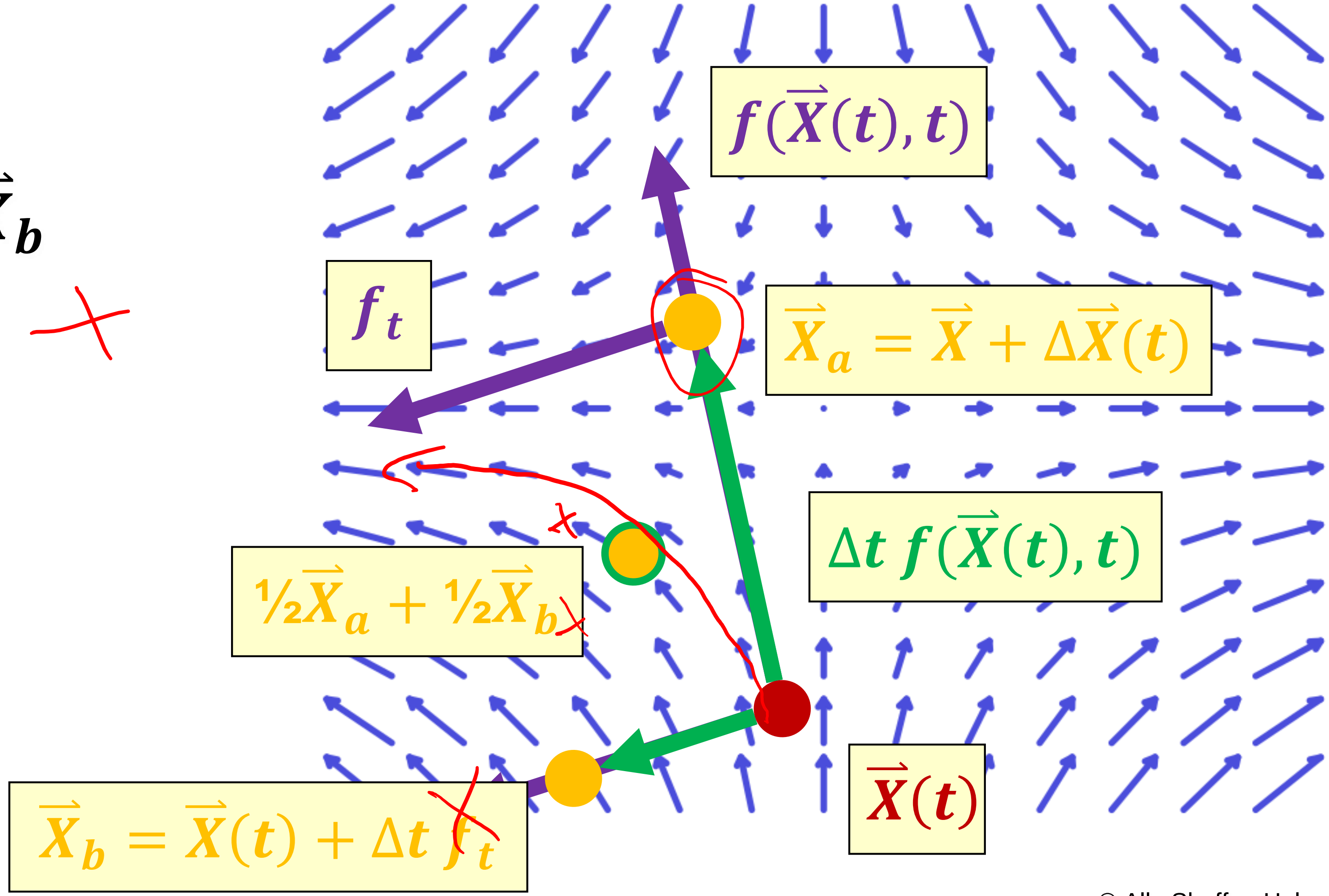
Midpoint Method

1. ½ Euler step
2. evaluate f_m at $\vec{X}_m$
3. full step using f_m



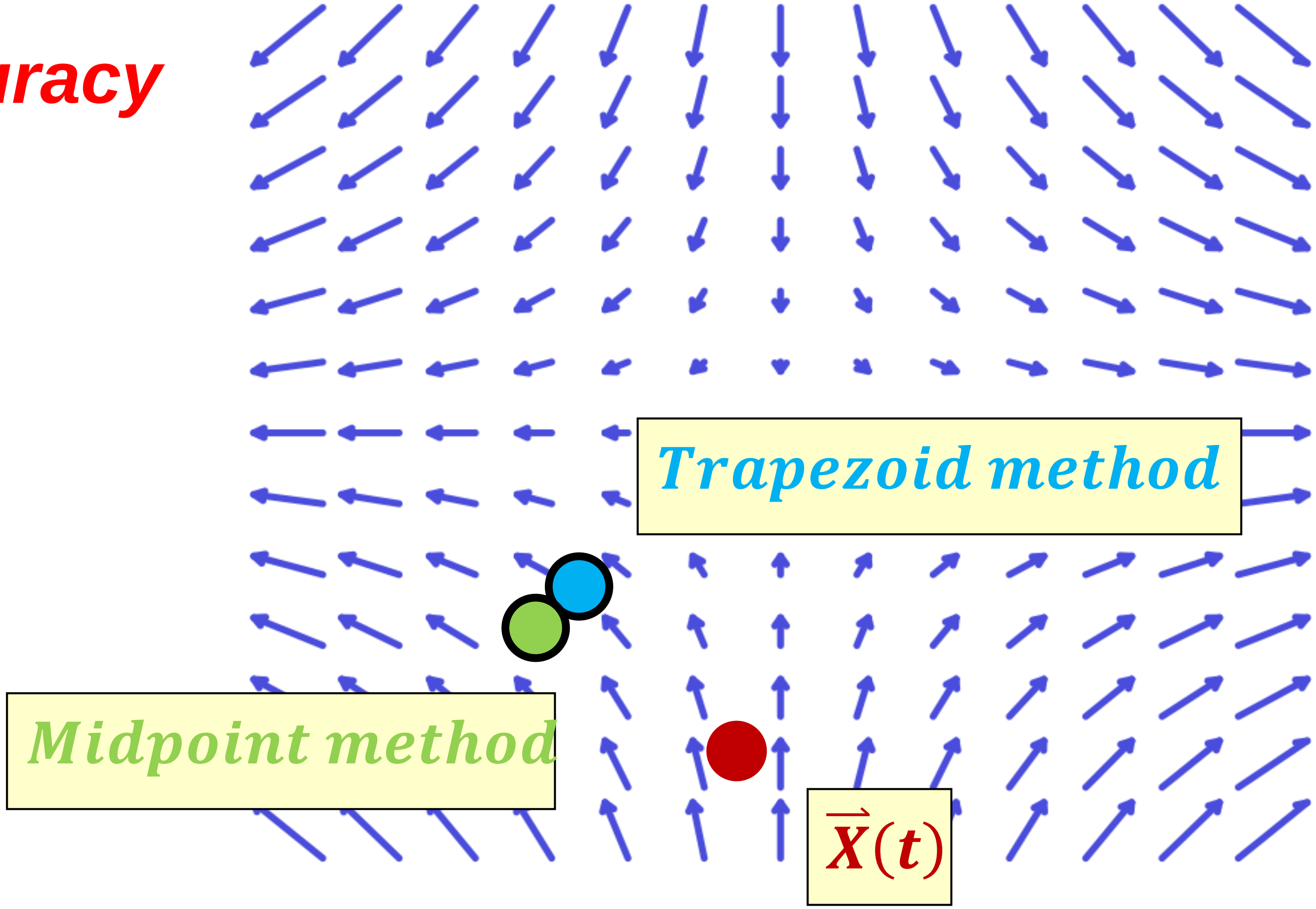
Trapezoid Method

1. full Euler step get $\vec{X}_a$
2. evaluate f_t at $\vec{X}_a$
3. full step using f_t get $\vec{X}_b$
4. average $\vec{X}_a$ and $\vec{X}_b$

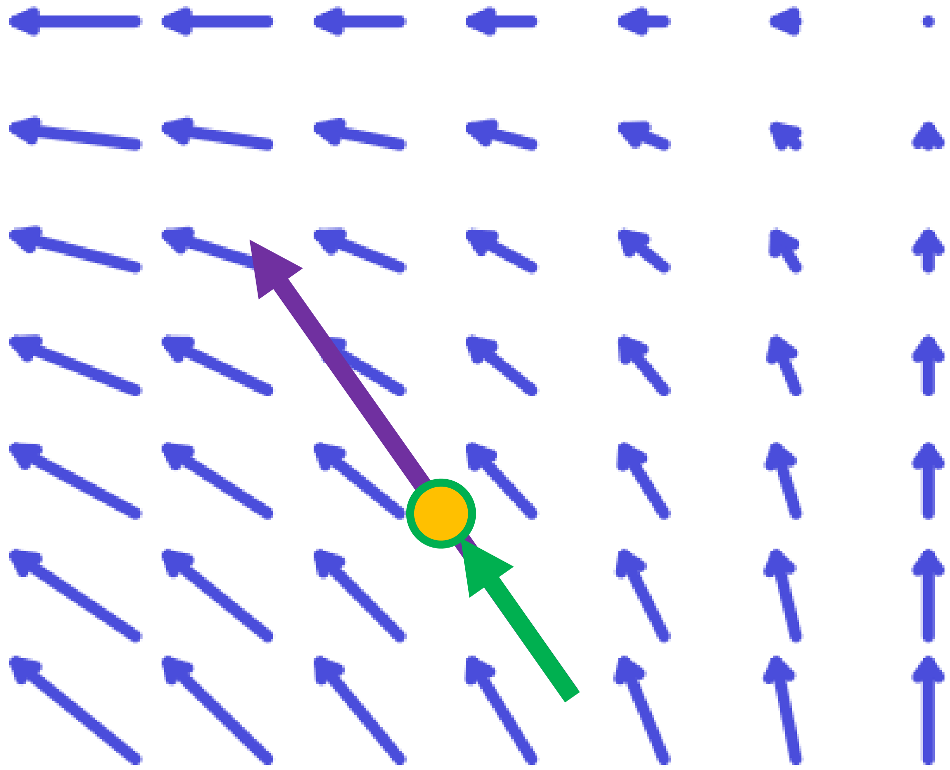


Midpoint & Trapezoid Method

- **Not exactly the same**
  - *But same order of accuracy*

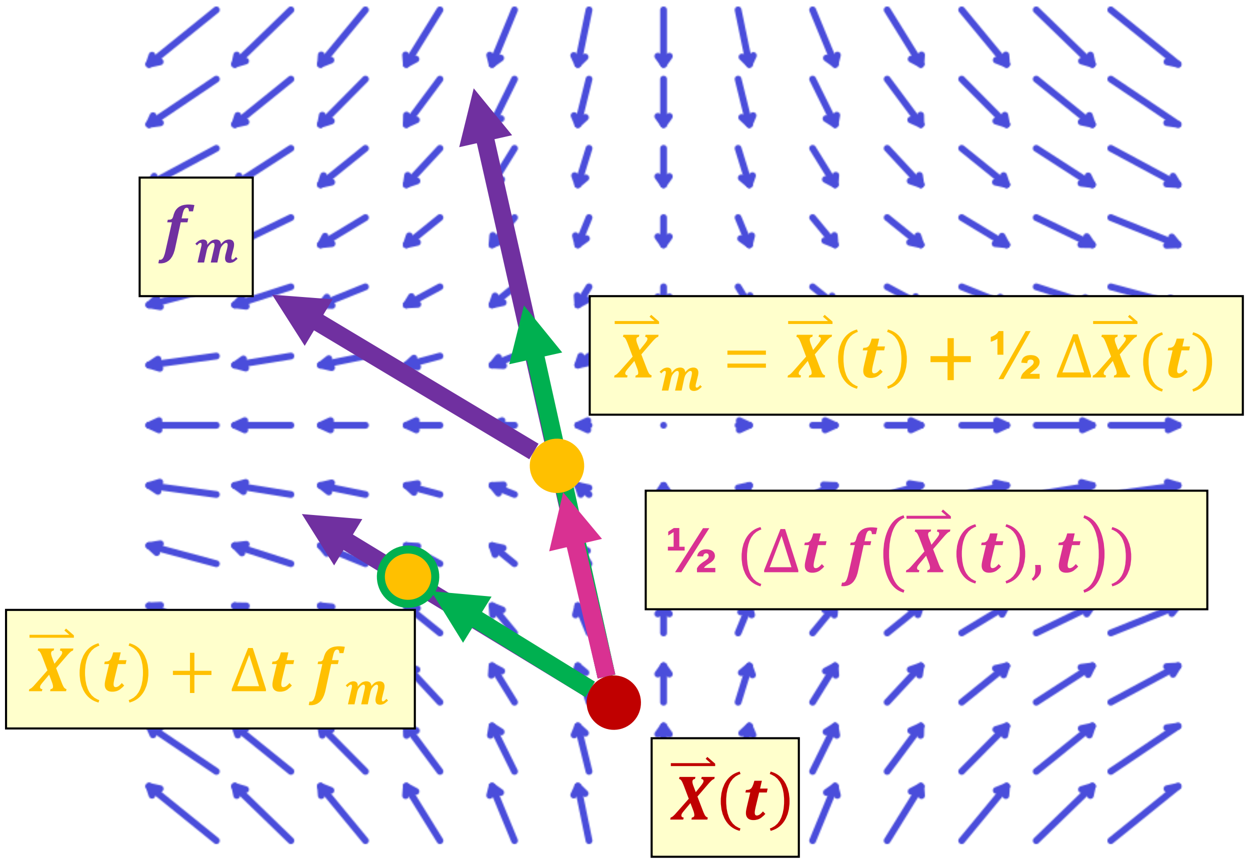


Explicit Euler: Code



```
void takeStep(ParticleSystem* ps, float h)
{
        velocities = ps->getStateVelocities()
        positions = ps->getStatePositions()
        forces = ps->getForces(positions, velocities)
        masses = ps->getMasses()
        accelerations = forces / masses
        newPositions = positions + h*velocities
        newVelocities = velocities  + h*accelerations
        ps->setStatePositions(newPositions)
        ps->setStateVelocities(newVelocities)
}
```

Midpoint Method: Code




```
void takeStep(ParticleSystem* ps, float h)
{
        velocities = ps->getStateVelocities()
        positions = ps->getStatePositions()
        forces = ps->getForces(positions, velocities)
        masses = ps->getMasses()
        accelerations = forces / masses
        midPositions = positions + 0.5*h*velocities
        midVelocities = velocities  + 0.5*h*accelerations
        midForces = ps->getForces(midPositions, midVelocities)
        midAccelerations = midForces / masses
        newPositions = positions + h*midVelocities
        newVelocities = velocities  + h*midAccelerations
        ps->setStatePositions(newPositions)
        ps->setStateVelocities(newVelocities)
}
```

Implicit (Backward) Euler:

- **Use forces at destination**

Solve system of equations

$$\frac{\partial}{\partial t}\begin{bmatrix}\vec{x}\\ \vec{v}\end{bmatrix} = \begin{bmatrix}\vec{v}\\ \Sigma\vec{F}/m\end{bmatrix}$$

$$\boxed{\begin{aligned}\boldsymbol{x_{n+1}} &= \boldsymbol{x_n} + \boldsymbol{h}\,\boldsymbol{v_{n+1}}\\ \boldsymbol{v_{n+1}} &= \boldsymbol{v_n} + \boldsymbol{h}\left(\frac{\boldsymbol{F_{n+1}}}{\boldsymbol{m}}\right)\end{aligned}}$$

- **Types of forces:**
  - ***Gravity***

    $$F = \begin{bmatrix}0\\ -mg\end{bmatrix}$$

  - ***Viscous damping***

    $$F = -bv$$

  - ***Spring & dampers***

    $$F = -kx - bv$$

Implicit (Backward) Euler:

- Use forces at destination + derivative at the destination

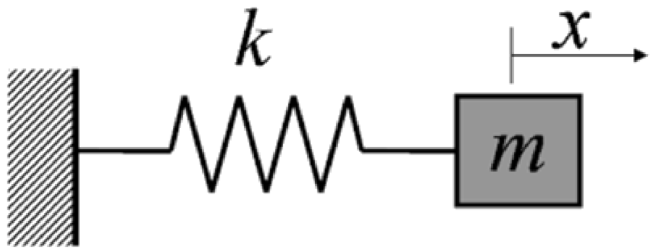
Solve system of equations

$$\frac{\partial}{\partial t}\begin{bmatrix}\vec{x}\\ \vec{v}\end{bmatrix} = \begin{bmatrix}\vec{v}\\ \Sigma\vec{F}/m\end{bmatrix}$$

$$\boxed{\begin{aligned} x_{n+1} &= x_n + h\, v_{n+1} \\ v_{n+1} &= v_n + h\left(\frac{F_{n+1}}{m}\right)\end{aligned}}$$

Example: Spring Force

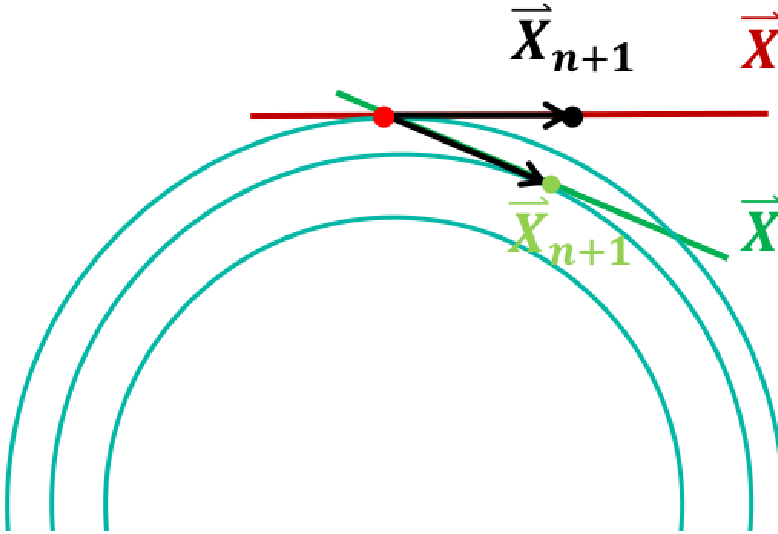
$F = -kx$



$$\boxed{\begin{aligned} x_{n+1} &= x_n + h\, v_{n+1} \\ v_{n+1} &= v_n + h\left(\frac{-k\, x_{n+1}}{m}\right)\end{aligned}}$$

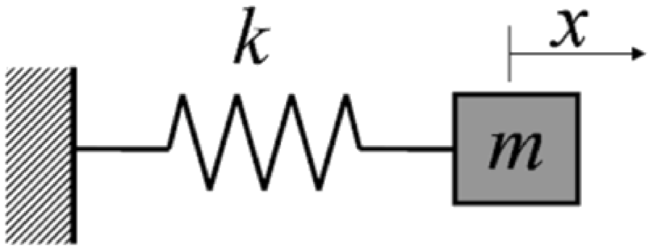
Analytic or iterative solve?

Forward vs Backward



$$\vec{X}_{n+1} = \vec{X}_n + \Delta t\, f(\vec{X}_n)$$

$$\vec{X}_{n+1} = \vec{X}_n + \Delta t\, f(\vec{X}_{n+1})$$



Forward Euler

$$x_{n+1} = x_n + h\, v_n$$
$$v_{n+1} = v_n + h\left(\frac{-k\, x_n}{m}\right)$$

Backward Euler

$$x_{n+1} = x_n + h\, v_{n+1}$$
$$v_{n+1} = v_n + h\left(\frac{-k\, x_{n+1}}{m}\right)$$

Could one apply the Trapezoid Method?

Particles: Newtonian Physics as First-Order DE

- **Motion of many particles?**

$$\frac{\partial}{\partial t}\begin{bmatrix}\vec{x_1}\\ \vec{v_1}\\ \vec{x_2}\\ \vec{v_2}\\ \vdots\\ \vec{x_n}\\ \vec{v_n}\end{bmatrix}=\begin{bmatrix}\vec{v_1}\\ \vec{F_1}/m_1\\ \vec{v_2}\\ \vec{F_2}/m_2\\ \vdots\\ \vec{v_n}\\ \vec{F_n}/m_n\end{bmatrix}$$

- **Interaction of particles?**

Multiple-particle collision

- ***naïve implementation is likely unstable***
  - *Objects pushing inside each other*

- ***Further reading:***
- https://box2d.org/publications/
  - *In particular https://box2d.org/files/ErinCatto_ModelingAndSolvingConstraints_GDC2009.pdf*

Simulation Basics

Simulation loop…

1. ***Equations of Motion***
2. ***Numerical integration***
3. ***Collision detection***
4. ***Collision resolution***

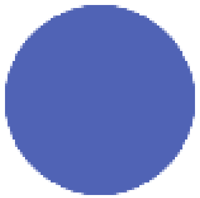
Collisions

- Collision detection
  - *Broad phase: AABBs, bounding spheres*
  - *Narrow phase: detailed checks*
- Collision response
  - *Collision impulses*
  - *Constraint forces: resting, sliding, hinges, ….*

Basic Particle Simulation (first try)

Forces only $\vec{F} = ma$

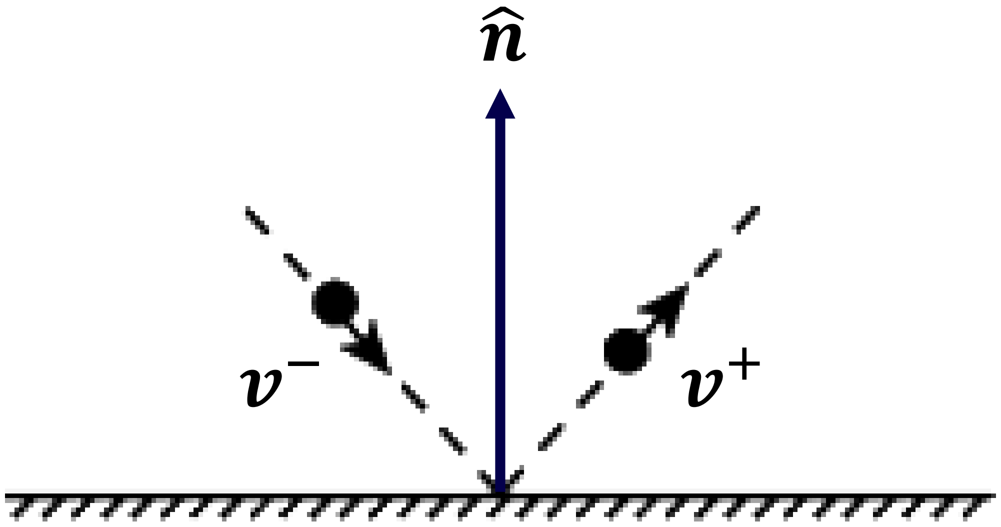
$$d_t = t_{i+1} - t_i$$
$$\vec{v}_{i+1} = \vec{v}(t_i) + (\vec{F}(t_i)/m)d_t$$
$$\vec{p}_{i+1} = \vec{p}(t_i) + \vec{v}(t_{i+1})d_t$$



Particle-Plane Collisions

- ***Apply an 'impulse' of magnitude j***
  - Inversely proportional to mass of particle
- ***In direction of normal***

Impulse in physics: Integral of F over time
In games: an instantaneous step change (not physically possible), i.e., the force applied over one time step of the simulation



$$j = (1+\epsilon)(v^- \cdot \hat{n})m$$

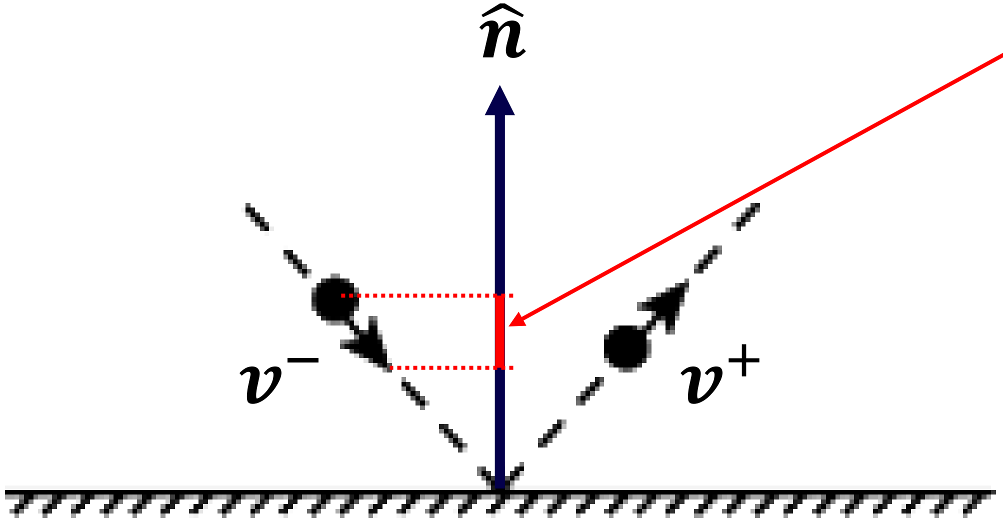
What is the effect of ϵ ?

$$\vec{j} = j\,\hat{n}$$

$$v^+ = \frac{\vec{j}}{m} + v^-$$

Recap: Particle-Plane Collisions (in terms of vel.)

- ***Change in direction of normal***



Velocity along normal (v projected on normal by the dot product)

Frictionless

Apply change along normal (magnitude times direction)

$$\Delta v = 2(v^- \cdot \hat{n})\hat{n}$$

$$v^+ = v^- + \Delta v$$

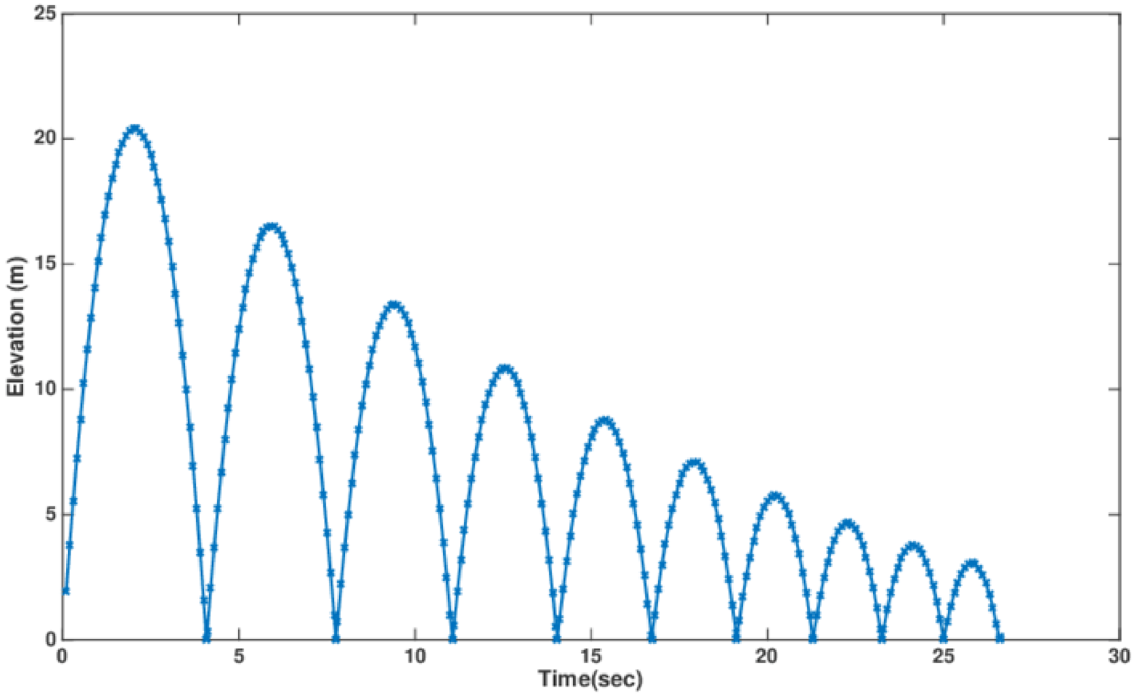
Loss of energy

$$\Delta v = (1 + \epsilon)(v^- \cdot \hat{n})\hat{n}$$

Why use 'Impulse'?

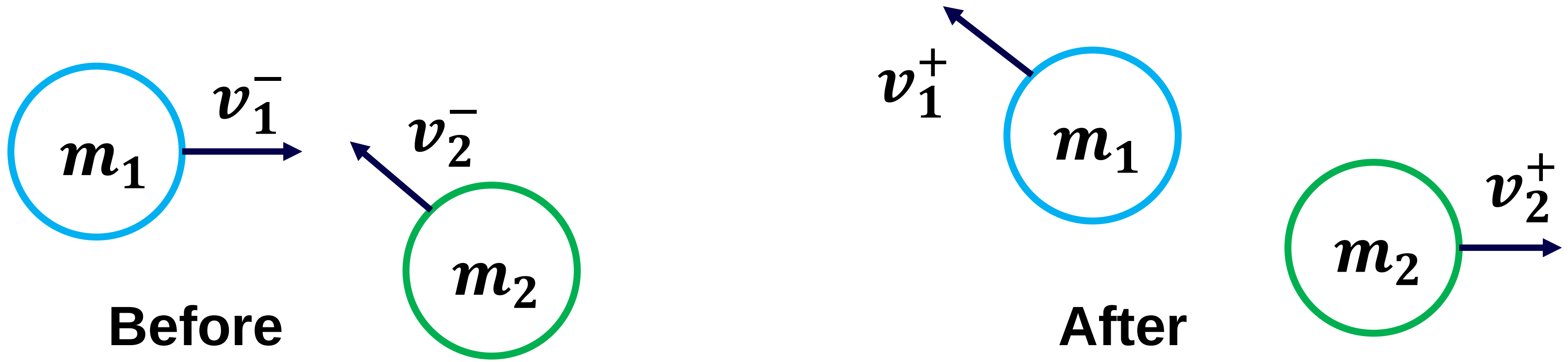
- ***Integrates with the physics solver***

- ***How to integrate damping?***



Particle-Particle Collisions (radius=0)

- Particle-particle **frictionless elastic impulse response**



- Momentum is **preserved**

$$m_1 v_1^- + m_2 v_2^- = m_1 v_1^+ + m_2 v_2^+$$

- Kinetic energy is **preserved**

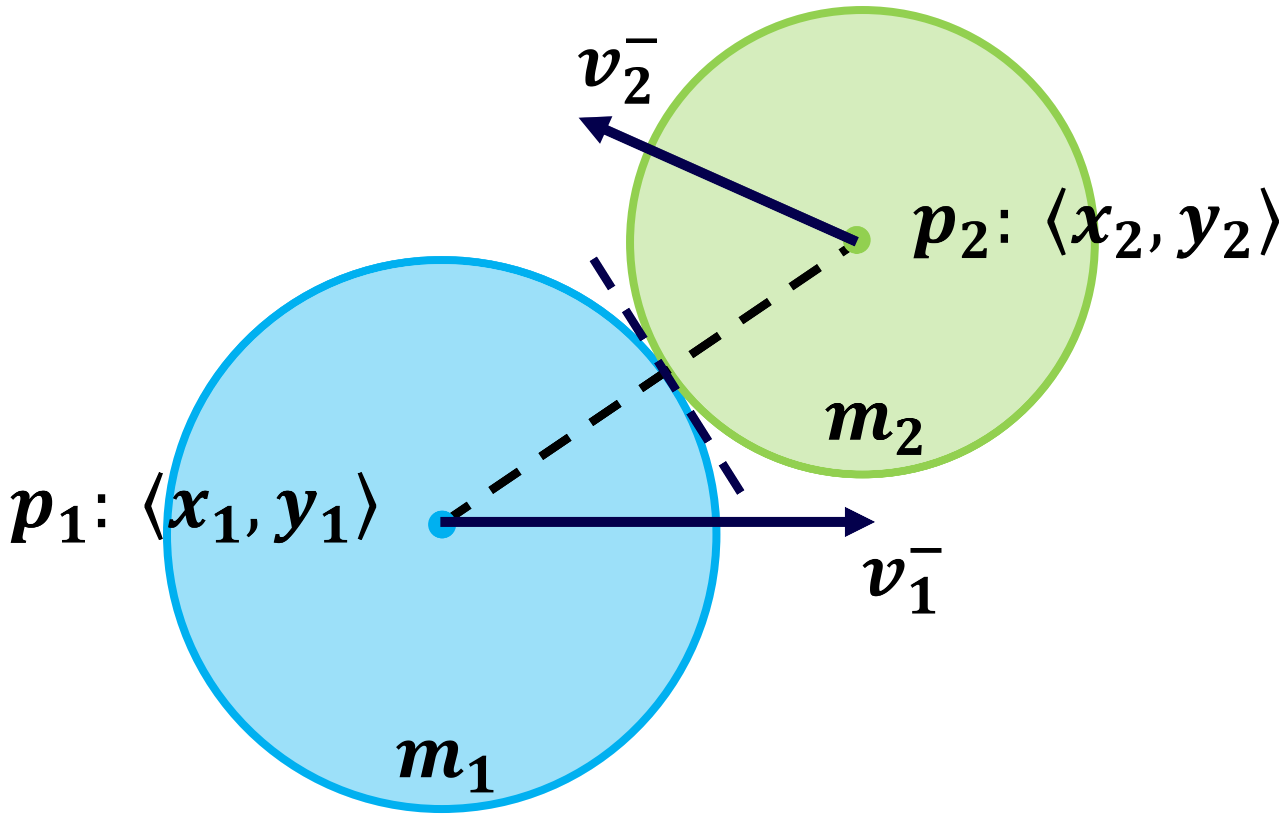
$$\tfrac{1}{2} m_1 {v_1^-}^2 + \tfrac{1}{2} m_2 {v_2^-}^2 = \tfrac{1}{2} m_1 {v_1^+}^2 + \tfrac{1}{2} m_2 {v_2^+}^2$$

- Velocity is **preserved in tangential direction**

$$t \circ v_1^- = t \circ v_1^+ , \qquad t \circ v_2^- = t \circ v_2^+$$

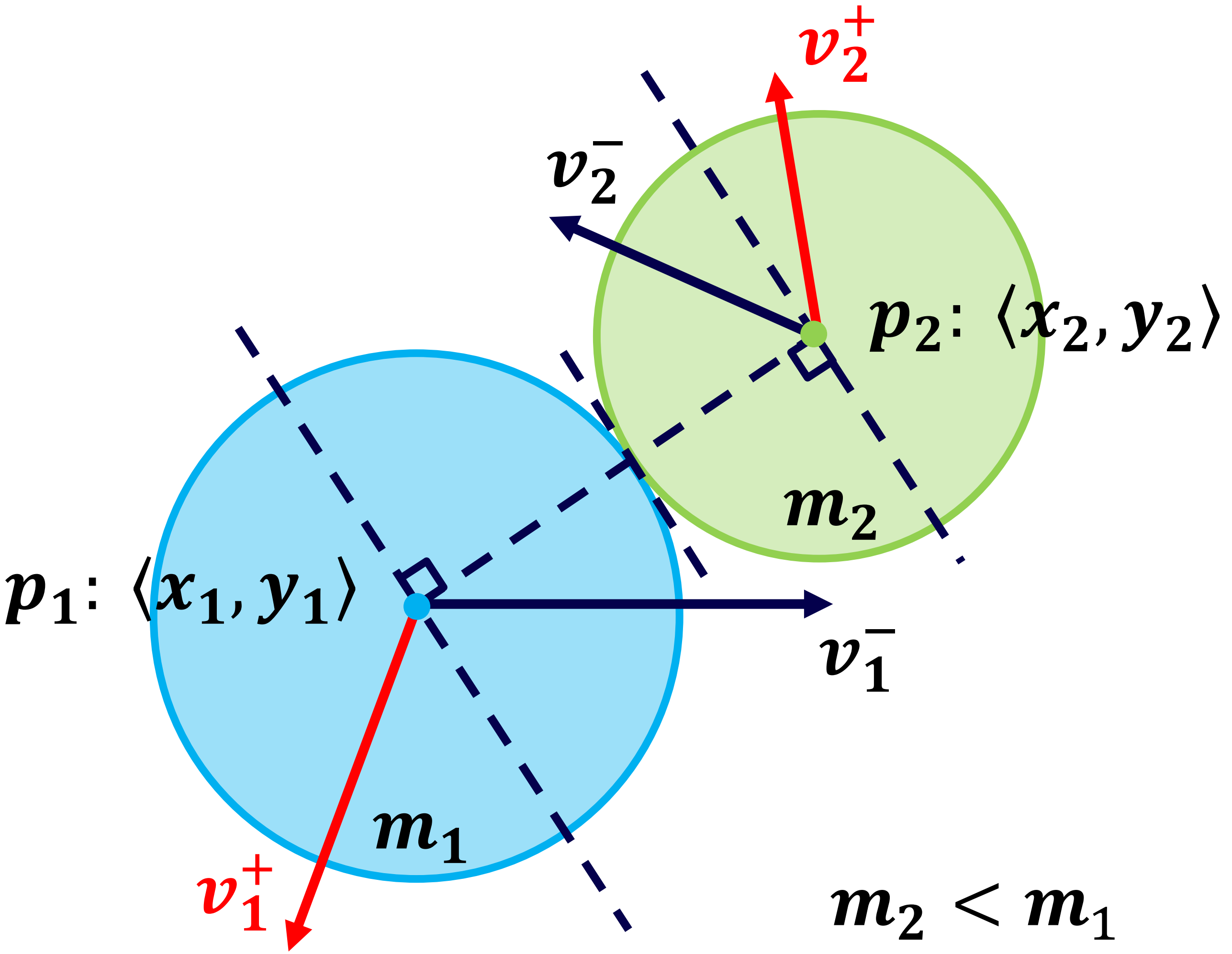
Particle-Particle Collisions (radius >0)

- What we know…
  - *Particle centers*
  - *Initial velocities*
  - *Particle Masses*
- What we can calculate…
  - *Contact normal*
  - *Contact tangent*



Particle-Particle Collisions (radius >0)

- Impulse direction reflected across tangent
- Impulse magnitude proportional to mass of other particle



Particle-Particle Collisions (radius >0)

- **More formally…**

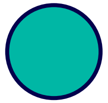
$$\boldsymbol{v}_1^+ = \boldsymbol{v}_1^- - \frac{2\boldsymbol{m}_2}{\boldsymbol{m}_1 + \boldsymbol{m}_2} \frac{\langle \boldsymbol{v}_1^- - \boldsymbol{v}_2^- \rangle \cdot \langle \boldsymbol{p}_1 - \boldsymbol{p}_2 \rangle}{\|\boldsymbol{p}_1 - \boldsymbol{p}_2\|^2} \langle \boldsymbol{p}_1 - \boldsymbol{p}_2 \rangle$$

$$\boldsymbol{v}_2^+ = \boldsymbol{v}_2^- - \frac{2\boldsymbol{m}_1}{\boldsymbol{m}_1 + \boldsymbol{m}_2} \frac{\langle \boldsymbol{v}_2^- - \boldsymbol{v}_1^- \rangle \cdot \langle \boldsymbol{p}_2 - \boldsymbol{p}_1 \rangle}{\|\boldsymbol{p}_2 - \boldsymbol{p}_1\|^2} \langle \boldsymbol{p}_2 - \boldsymbol{p}_1 \rangle$$

- This is in terms of velocity, what would the corresponding impulse be?

Rigid Body Dynamics (rotational motion of objects?)

- **From particles to rigid bodies…**



Particle

$$state = \begin{cases} \vec{x}\ position \\ \vec{v}\ velocity \end{cases}$$

$\mathbb{R}^4$ in 2D
$\mathbb{R}^6$ in 3D

Rigid body

$$state = \begin{cases} \vec{x}\ position \\ \vec{v}\ velocity \\ R\ rotation\ matrix\ 3x3 \\ \vec{w}\ angular\ velocity \end{cases}$$

$\mathbb{R}^{12}$ in 3D