

Introduction to Virtual Reality Part II

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1/86

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Content



- Introduction
- Input Systems
- **Virtual Reality Engine**
- World Generators
- Output Systems
- Applications

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2/86

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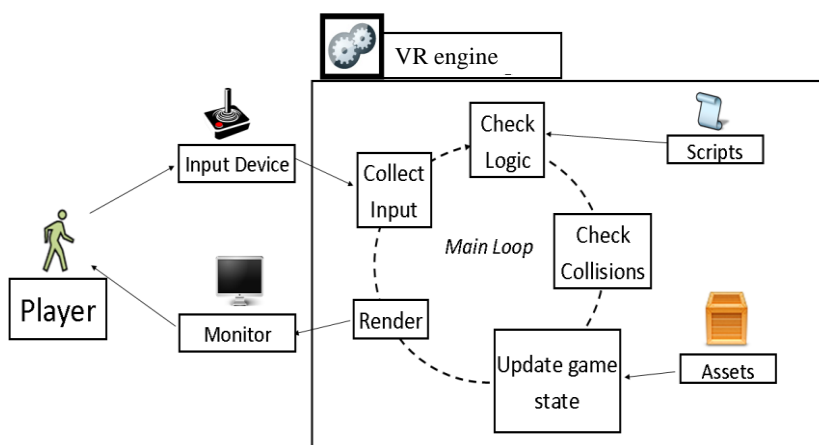
Sensorial stimulation



- Vision -> Graphical rendering
- Audio -> Audio rendering
- Proprioception -> Vibrators, gloves,...
- Olfactory
-



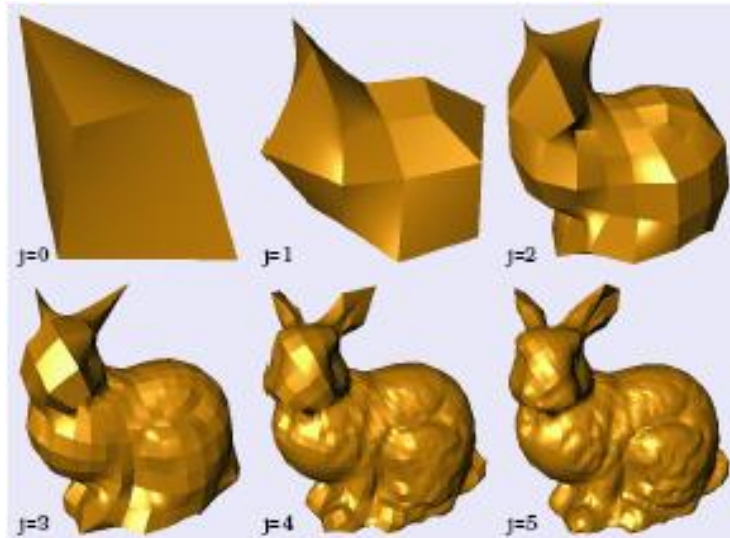
What is a VR engine?



It is a game engine!



LOD models



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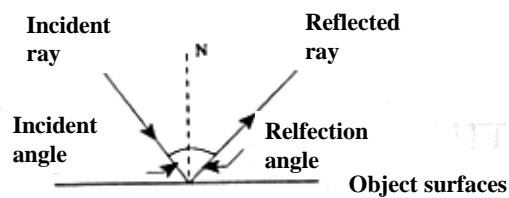


Rendering

Precompute that "renders", that is generates, an image starting from the Mathematical description of a 3D scene, through algorithms that define the color in each point of the digital image [Wikipedia].

Rendering is based on the physics of the (electromagnetic) waves that describes the interaction between the waves and the interacting mean, causing reflections, refraction, scattering, tunnelling effects...).

We see what is **sent back (reflected)** by the scene => The scene is lit by one or more lights (not light, no image), that is reflected by objects and hits the image plane.



We see what hits our eyes!

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The VR engine (visual computing)



Double buffering (for real-time visualization of 3D models) + rasterization.
Quad-buffering from VR.

Interpolation of normals direction among adjacent triangles (to create the appearance of a continuous curved surface)

Graphical pipelining (from 3D geometry to 2D images: projection, colour, texture, shadowing, ...).

Parallelization. GPU programming language (CUDA nVidia).

Hierarchy of structures (objects, collision detection...)

Multiple cache levels.

Look-ahead code optimization (compiler optimization).



Collision detection



Computational demanding ($O(n^2EF)$).

Use of multiresolution models.

Hierarchical detection.

- Geometry simplification (axes aligned faces).

- Check for common volumes.

- Extraction of the faces belonging to these volumes.

- Octree of the pairs of candidate faces.

- Check for intersection.

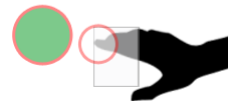


2D collision detection

- Collision detection with target can be checked by analyzing the overlapping between part of the motion mask only in particular regions.
- Identification of the motion mask as the outermost part of the body. Approximated collision detection defining general shapes.

Correct Hand collision area
(most left pixel in the area around first top most high pixel)

- Collision with targets gives hit, collision with distractors gives a miss.
- Same principles implemented with Sony EyeToy Webcam (2003).



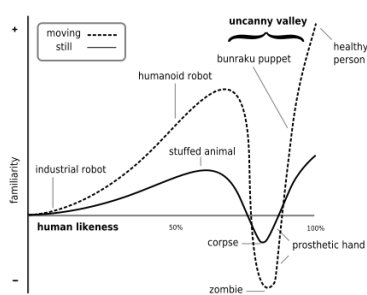
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Avatar designed avoiding the "uncanny" valley



Mori, Masahiro (1970). Bukimi no tani The uncanny valley (K. F. MacDorman & T. Minato, Trans.). Energy, 7(4), 33-35. (Originally in Japanese)



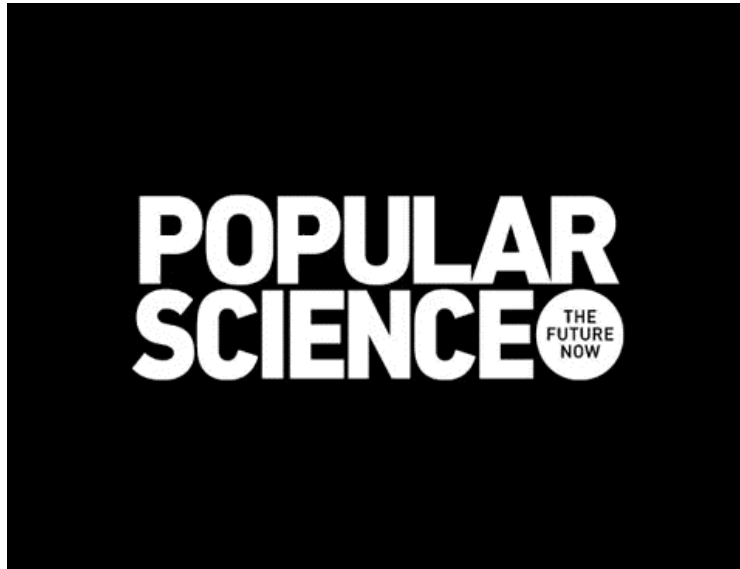
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Uncanny Valley



Content



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3D Assets making



- Scanners 3D (copying from reality)
 - Active (laser or unstructured light, sound)
 - Passive (video - SLAM)
- Modelling
 - Organic
 - Non organic
- Procedural content generation

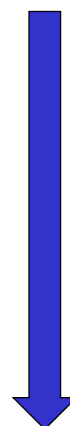


VR related engines



- Graphics Library:
 - OpenGL
 - DirectX
- 2D /3D Graphical Engines:
 - Realtime
 - Ogre3D
 - Irrlicht
 - SDL/SFML
 - Non Realtime
 - Renderman (PIXAR)
 - Cycle (Blender)
- Software that use Graphical Engines:
 - 3D modeling
 - Blender
 - Maya
 - 3D Studio Max
 - Game Engines
 - Panda 3D
 - Unity 3D
 - Unreal
- VR Library:
 - VR Toolkit
 - OpenVR
 - Meta?

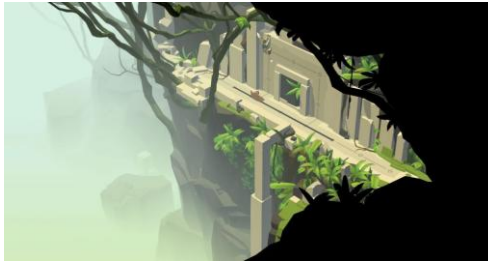
Low level



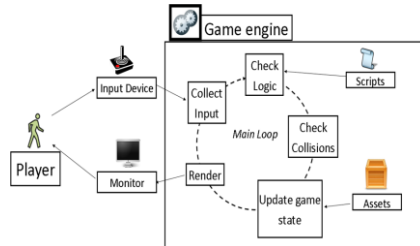
High Level



<http://unity3d.com>



Lara Croft go puzzle adventure



Rush game



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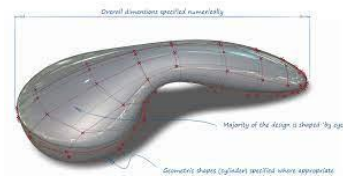
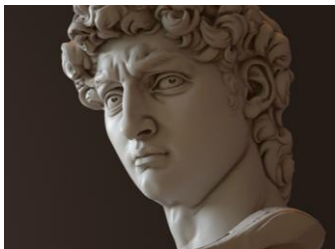


CAD systems



Softimage, Maya, Blender, Unity 3D, Unreal ...

- Polygonal modelling
- Curved modelling (e.g. NURBS)
- Volumetric modelling (sculpting)



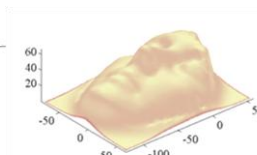
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3D Scanner: Autoscan - 1997



- Manual scanning through a laser pointer,
- Real-time display feed-back to guide scanning.
- Flexible set-up and portability
- Acquisition of laser spot in real-time at 100 Hz. (max 100 points / sec)
3D reconstruction of the spot through triangulation poses problems due to noise on the measurement of position on the cameras.

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Models from range data



Cyberware whole body scanner, WB4



Which problems do you envisage?

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Models from range data (II)



Cyberware smaller model
3030



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Models from range data (IV)



Digibot II.
•Platform rotates
•Scanner line translates.



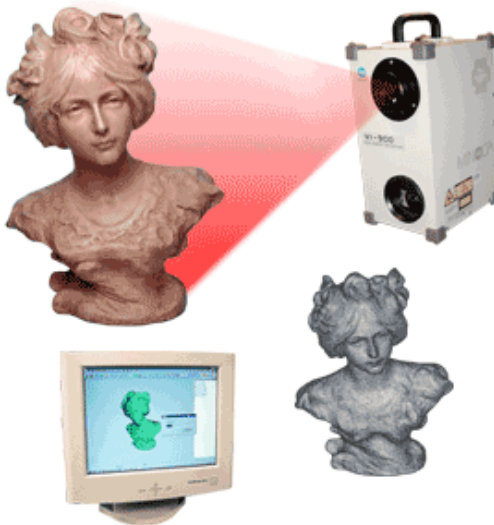
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MINOLTA
Scanner Laser 3d



Minolta scanner 3D

https://www.konicaminolta.com/instruments/download/instruction_manual/3d/index.html

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3D structure from range data (III)



Polhemus hand held laser scanner

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From Clouds to surfaces



Effect of measurement noise is clear with Delaunay triangulation.
Need of filtering is evident.



3D structure from points

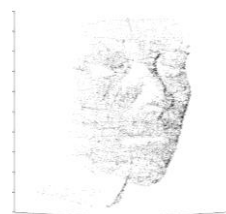


Linear approximation (mesh):

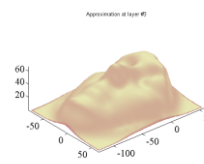
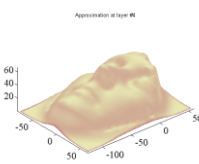
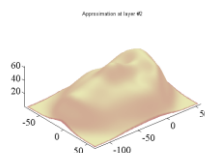
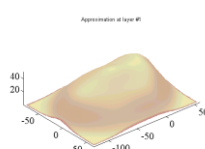
- Delaunay triangulation (Watson, 1981; Fang and Piegl, 1992). Direct tessellation (no filtering).
- Alpha shapes, Ball Pivoting (Bernardini et al., 2000), Power Crust (median axis transform, Amenta, 2002). Post processing to regularize a Delaunay tessellation.

Surface fitting to range data

- Snakes (Kass et al., 1988). Energy based approach. Best curves.
- Kohonen maps (1990).
- Radial Basis Functions Networks (Poggio and Girosi, 1995; Ferrari et al. 2005, semi-parametric models, incremental approach).
- Support Vector Regression (SVR, A.Smola and B.Scholkopf)

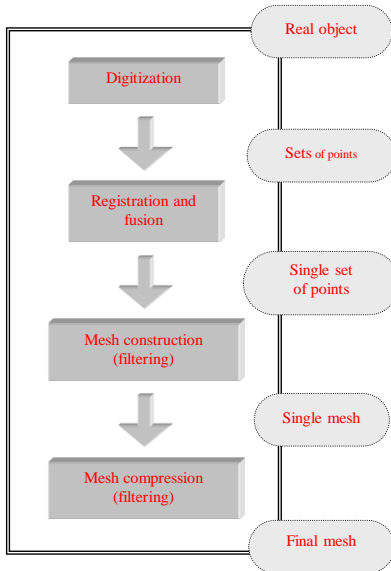


.....





Scanner 3D modern pipeline



M. Levoy, S. Rusinkiewicz, M. Ginzton, J. Ginsberg, K. Pulli, D. Koller, S. Anderson, J. Shade, B. Curless, L. Pereira, J. Davis and D. Fulk, "The Digital Michelangelo Project: 3D Scanning of Large Statues," *Proc. Siggraph '99*, ACM Press, pp. 121-132, 1999



Research challenges Digital Michelangelo project



- vision problems
 - aligning and merging scans
 - automatic hole filling
 - inverse color rendering
 - automated view planning
 - Interaction of laser with marble
- digital archiving problems
 - making the data last forever
 - robust 3D digital watermarking
 - indexing and searching 3D data
 - real-time viewing on low-cost PCs



Video-based 3D scanner (Rusinkiewicz et al., 2002)



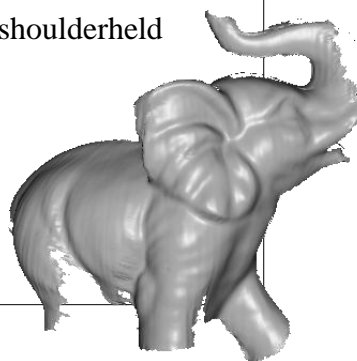
- A projector of stripes with pseudo-random width and a video camera
- holes can be found and filled on-the-fly
- object or scanner can be handheld / shoulderheld



video frame



range data



merged model
(159 frames)

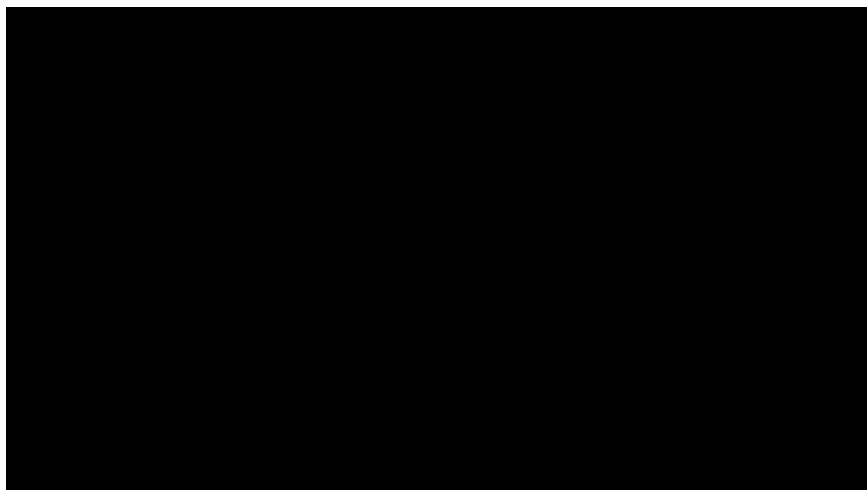
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Kinect fusion



Low cost 3D modeling

KinectFusion: Real-time 3D Reconstruction and Interaction

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Using a Moving Depth Camera, Izadi et al., Proc. Siggraph 2011

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3D modelling



Solid modeling

- 3D geometric solids: cubes, cylinders, cones...
- Revolution surfaces.
- Spline and NURBS (Piegle, 1993). CAD, high interactivity.
- Subdivision surfaces (Schroeder, 1999).
- Hierarchy of objects with heritage.

Rendering

- Colour and Texture
- lights => shadows.

Animation

- Motion (animation)
- Camera tracking (for augmented reality), transparencies....

Specialized systems: Finite element models

- It is a class per sé. Local modeling. Mechanical modeling.
- Largely used for animation in medicine (facial animation, deformation of tissue during surgery). Multi-layer modeling.
- Specialized SW are usually associated: Katia, AutoCAD...
- 3D Structure.

Specific CAD for mechanics: Katia, AutoCAD, Nastran SW => **Visual Computing**



Procedural Modelling



Models generated through a procedure (a software program, an algorithm)

It is possible to construct a 3D mesh specifying parametric rules to create the objects.

Examples: Trees, Cities, Mugs,



Artificial plants



A synthetic model of the topiary garden at Levens Hall, England, by

R. Mëch, P. Prusinkiewicz, and M. James. "Garden of L" (inset) by P. Prusinkiewicz,

F. Fracchia, J. Hanan, and D. Fowler; see www.cpsc.ucalgary.ca/~pwp

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Realizing a plant



Lindenmayer example

variables : X F

constants : + - []

start : X

rules : $(X \rightarrow F - [[X] + X] + F [+FX] - X), (F \rightarrow FF)$

angle : 25°

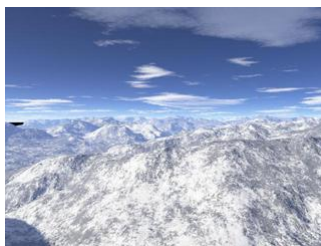
Here, F means "draw forward", - means "turn left 25°", and + means "turn right 25°". X does not correspond to any drawing action and is used to control the evolution of the curve.

[corresponds to saving the current values for position and angle, which are restored when the corresponding] is executed.





Specific SW for terrain modelization (Terragen)



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Artificial landscape



<http://planetside.co.uk/products/terragen3>



Video on Vajont history

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Content



- Introduction
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Haptic displays



Convey to the subject the sensorial information generated in the interaction with the virtual objects: force, material texture...

Measure the force exerted by the subject on the virtual environment.

Haptic displays provide a mechanical interface for Virtual Reality applications.

Most important developments have been made in the robotics field.

International Haptic society - <http://www.isfh.org/>



Direct drive manipulandum (phantom)



Geomagic® Phantom® Premium
(ex Sensable Techn. 1993-2012) Now 3D Systems
A similar device (Falcon) is available and used in our lab for rehabilitation



Haptics low cost



Omni Phantom



Novint Falcon

Experience in the lab



Requirements of Haptic displays



- Large bandwidth.
- Low inertial and viscosity.

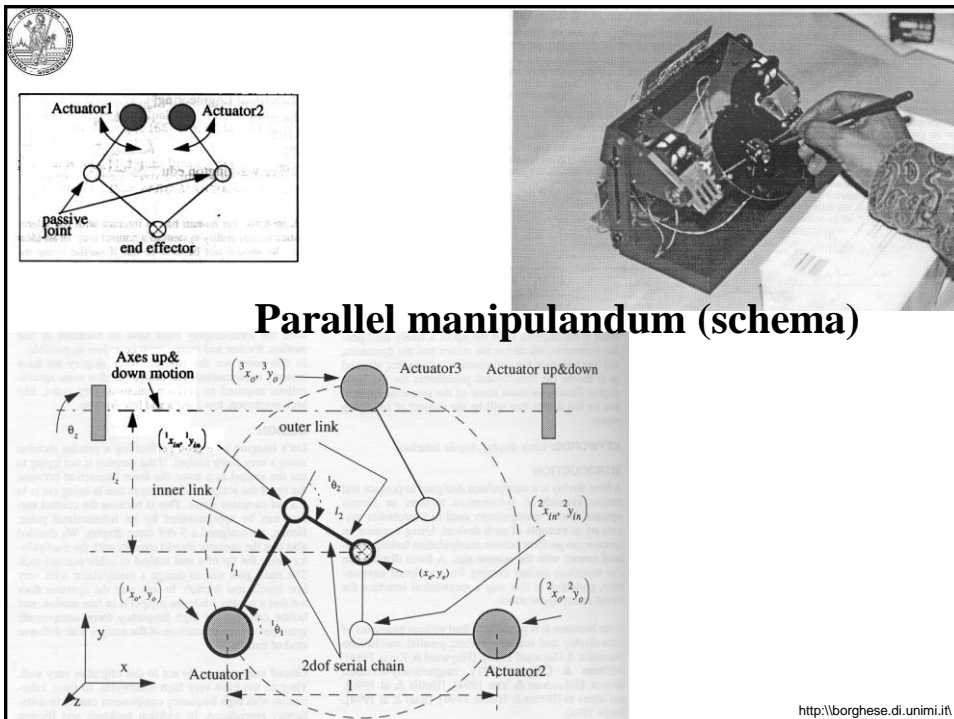
Technological solutions (oggetto intermediario):

- Direct drive manipulandum (Yoshikawa, 1990), Phantom (2000).
- Parallel manipulandum (Millman and Colgate, 1991; Buttolo and Hannaford, 1995).
- Magnetic levitation devices (Salcudean and Yan, 1994; Gomi and Kawato, 1996).
- Gloves and esoskeleta (Bergamasco, 1993, MITmanus, 2000, Braccio di ferro, 2007).

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MIT-Manus, 2004



Braccio di ferro, 2010



Support for the fore-arm, and generation of a force field.

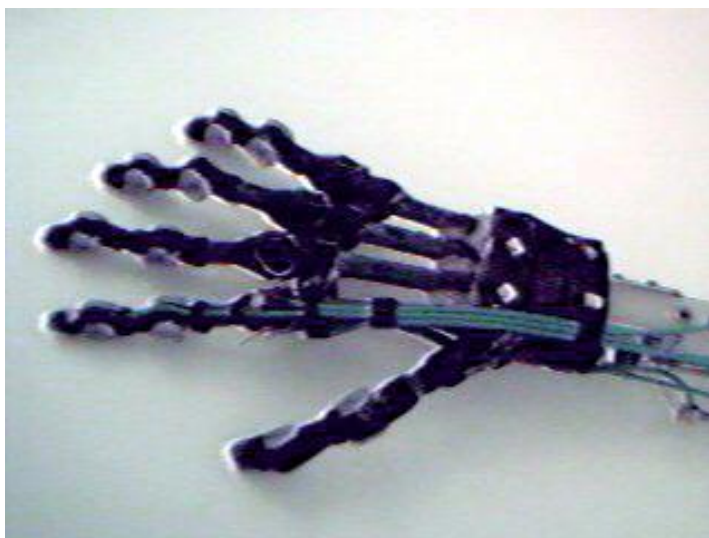
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Gloves (Blackfinger, 2000)



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44/86

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Percro glove (2002)



Sensori goniometrici – non devono essere calibrati sulla lunghezza delle falangi.

<http://www.percro.org>

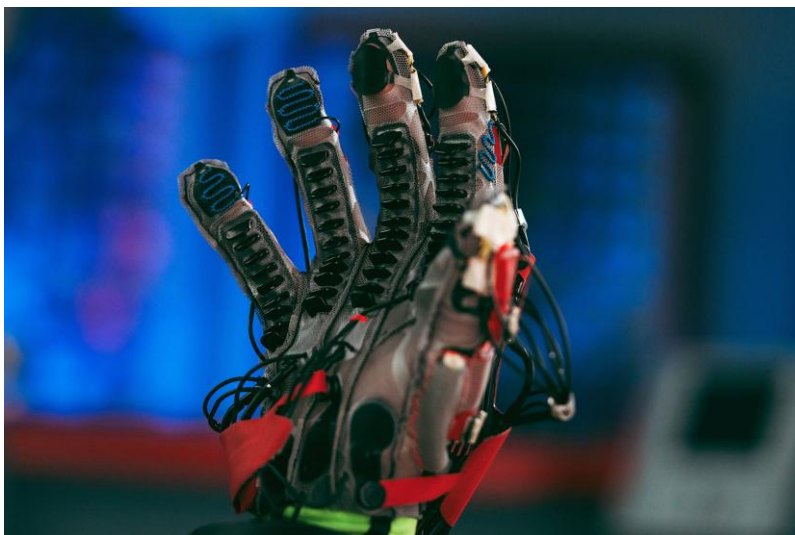
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Meta hand from Meta VR labs



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Tactile Stimulators

Cyber touch:

- 6 vibrators, 1 for each finger + 1 on palm
- Vibration frequency: 0-125 Hz.
- Vibration amplitude: 1.2 N @ 125 Hz (max).

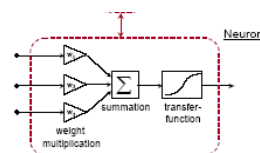
Iwamoto & Shinoda
University of Tokio



Other output devices

Audio – Stereo, sound spatialization.

Olfactory – Virtual nose



Type	Sensitive material	Detection principle
semiconducting metal oxides (M.O.S., Taguchi)	doped semiconducting metal oxides (SnO ₂ , GaO)	resistance change
quartz crystal microbalance, QMB	organic or inorganic layers (gas chromatography)	frequency change due to mass change
surface acoustic wave, SAW		
conducting polymers	modified conducting polymers	resistance change
catalytic field-effect sensors (MOSFET)	catalytic metals	workfunction change
pellistor	catalysts	temperature change due to chemical reactions
fluorescence sensors	organic dyes	light intensity changes
electrochemical cells	solid or liquid electrolytes	current or voltage change
infra red sensors	-	IR absorption



The future?



Impacto
Simulating Physical Impact by Combining
Tactile with Electrical Muscle Stimulation

Pedro Lopes, Alexandra Ion, and Patrick Baudisch

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Sistemi di Output::visione



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Optical Output systems



Requirements for the monitor:

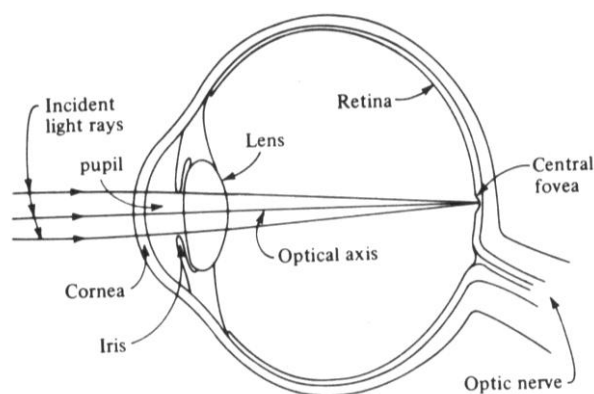
- Large field of view ($180^\circ \times 150^\circ$).
- High spatial resolution (35 pixels/degree, equivalent to 12,000x12,000 pixels for a 19" display positioned at 70cm from the viewer).

Requirements for the world generator:

- Stereoscopic vision for objects with $D < 10m$.
- Monocular cues for objects with $D > 10m$.
 - - Occlusions.
 - - Geometrical perspective and a-priori model knowledge.
 - - Shading.
 - - Motion.



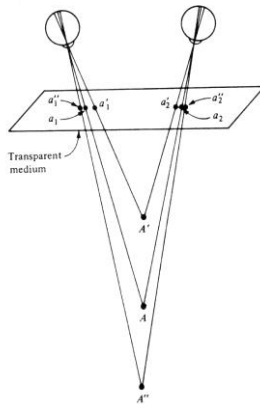
Human eye



Its behavior is very similar to that of a camera
Lens focuses the image, vergence movement orients the eye.



Vergence (stereo-disparity)



Points further away are projected on points closer to the image center.

The sum of these distances is called stereo-disparity and depends on distance.

Stereo-images should have this disparity.

Vergence and focusing are strictly connected.

Also monocular cues: shading, apparent size,



VR sickness



La dissonanza tra la percezione di movimento tra vari organi del nostro corpo, i quali mandano segnali contrastanti al nostro cervello che di conseguenza «va in confusione» e entra in modalità di protezione.

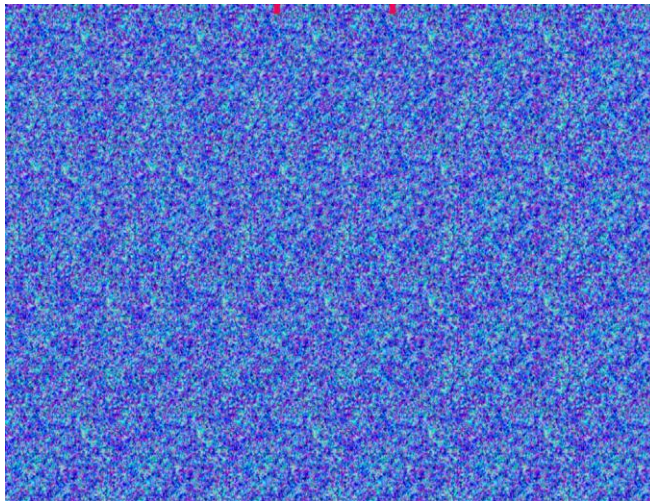
Conflitti sensoriali:

- Vergenza e messa a fuoco
- Movimento apparente dato dalla vista e assenza di movimento reale, determinato dall'apparato vestibolare e somatosensoriale.
 - **L'apparato vestibolare**, che tramite gli organi del Golgi determina l'accelerazione angolare (rotazione) della nostra testa nello spazio.
 - **La vista**, che elabora il movimento degli oggetti esterni rispetto al nostro corpo.
 - **L'apparato somatosensoriale** che tramite muscoli, pelle, tendini e articolazioni riceve informazioni sul movimento del corpo nello spazio.

Non riguardano la realtà aumentata



Autostereogram



To see the 3D image, you need to relax and to try to view "through" the image (focusing at infinity – rettile preistorico volante)

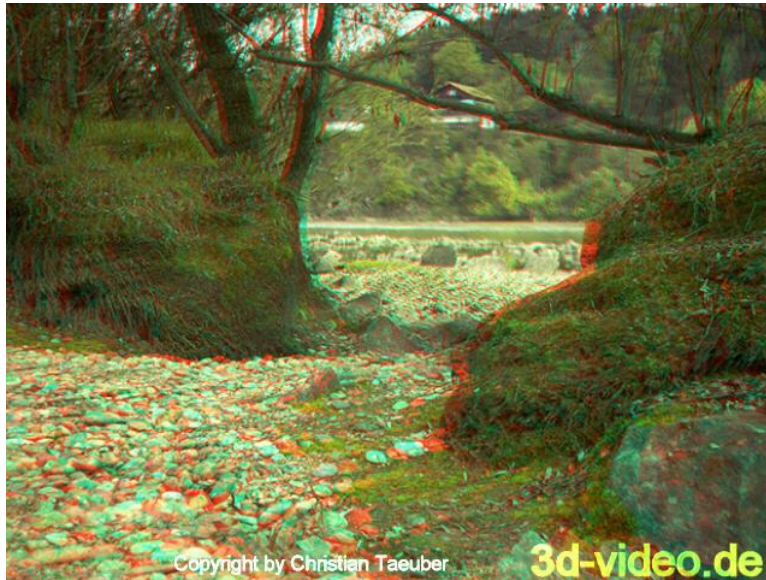


Passive stereo





Stereo image for passive stereo



Copyright by Christian Taeuber

3d-video.de

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57/86

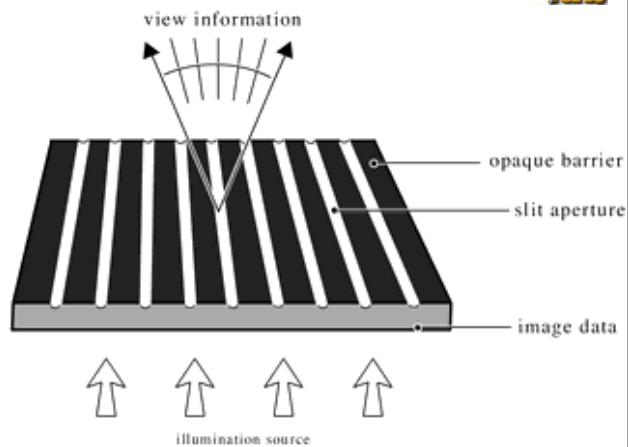
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Stereogram through parallax



Patent of 1903



The image is subdivided into vertical stripes.

Pairs of stripes congruent with a given angle of view are positioned in the proper columns under the lens.

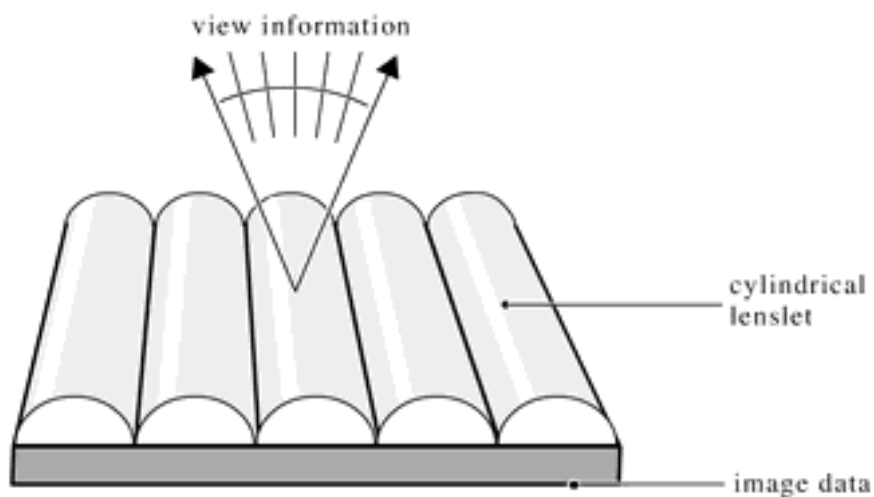
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Display Autostereoscopici



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59/86

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Output devices (eye-glasses)



Semi-immersive: Eye-glasses (video accuracy, but user is not allowed to move, lateral vision is permitted, which limits virtual realism).



Images are generated multiplexed in time for the two eyes.
Quad-buffering is used (a pair of double buffers).

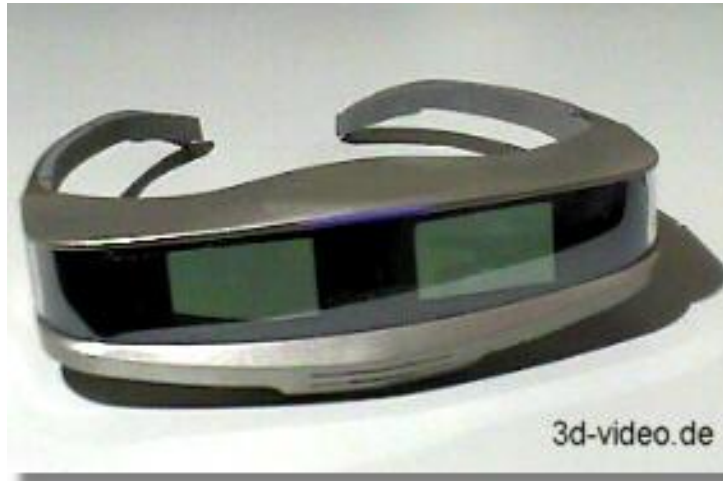
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I-glasses (games)



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61/86

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HMD (n-vision)



Up to 1280 x 1024, 180Hz.
Time multiplexing.

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62/86

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Output devices (BOOM HMD)



Up to 1280 x 1024 pixels / eye
CRT Technology
Head tracking is integrated.



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63/86

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CAVE



Room 2.5m x 2.5m
with Virtual images
(stereoscopic) projected
onto its walls.

More people and
Complete immersivity.



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Oculus Rift novel HMD: a new hype



Stereo
Motion
Face
Gaze



Experience in the lab
Thesis available

<http://www.oculusvr.com/>

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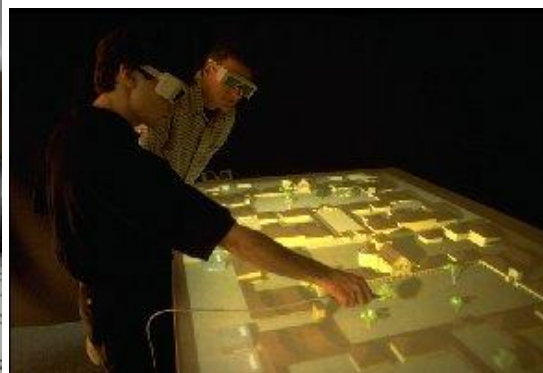
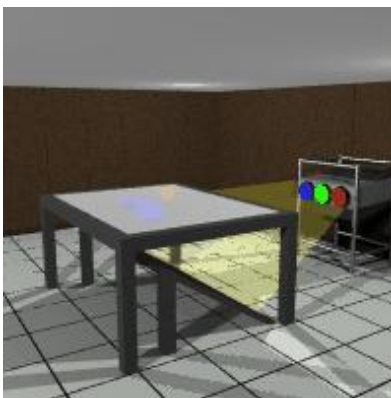
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Responsive work-bench (Strauss et al., 1995)

Virtual 3D objects are positioned on a working table. They are created projecting the stereo images over the table surface.



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66/86

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Large screen displays (with or without stereo – see Graphics Lab in Celoria)



Workwall



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Content



- Introduction
- Input Systems
- Graphical Engine
- World Generators
- Output Systems
- **Applications**

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68/86

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Applications



- Army
- Medicine
- Industry (inspection, virtual prototyping)
- Chemistry and Physics
- Virtual theaters and theme parks
- Entertainment
- Communication
- Engineering, Ergonomics and Architecture (Visual computing).
- History.



Nefertari





Virtual mannequin



Amazon virtual dressing room: <https://www.youtube.com/watch?v=X3ghb6atM2o>

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71/86

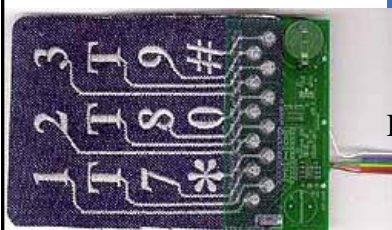
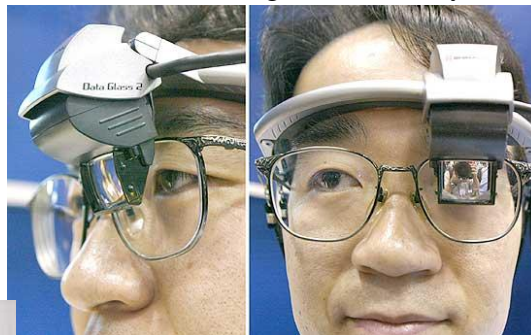
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Wearable devices – input / output



Characteristics: mobile, context sensitive, augmented reality.



Interface on cloth

72/86

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Design: virtual industrial plans



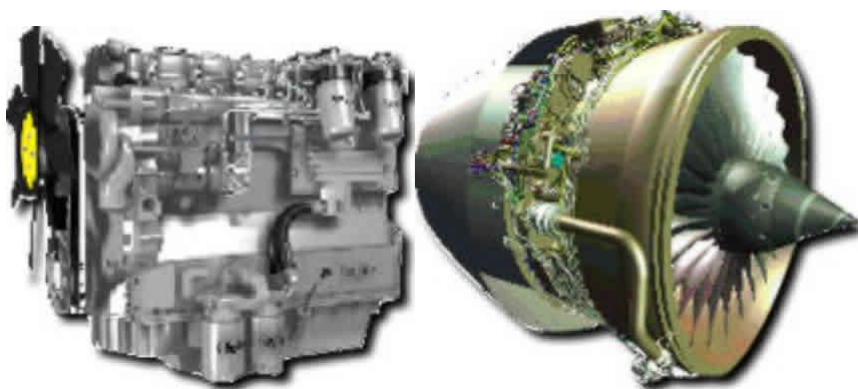
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73/86

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Design: virtual engines



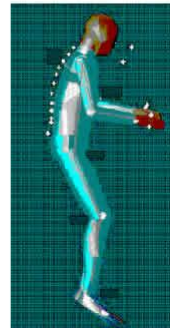
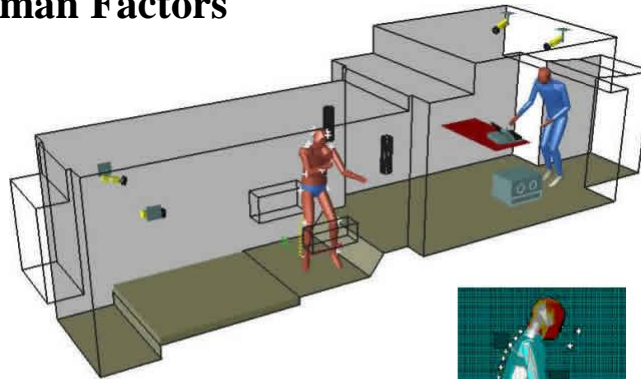
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74/86

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Human Factors



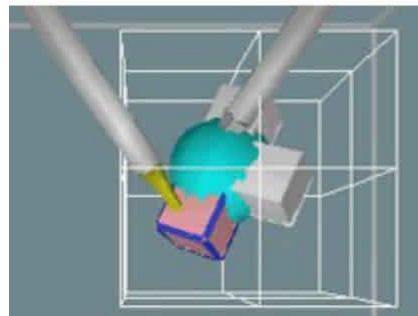
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75/86

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Assisted surgery



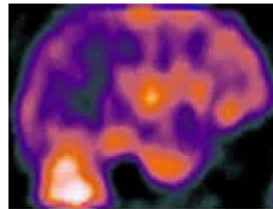
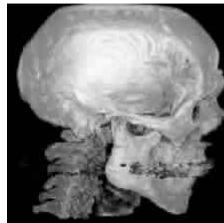
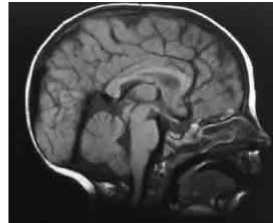
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76/86

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Surgery planning through imaging



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77/86

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Imaging and 3D printing



Acrylic mandible realized with CAD-CAM technology from CAT images

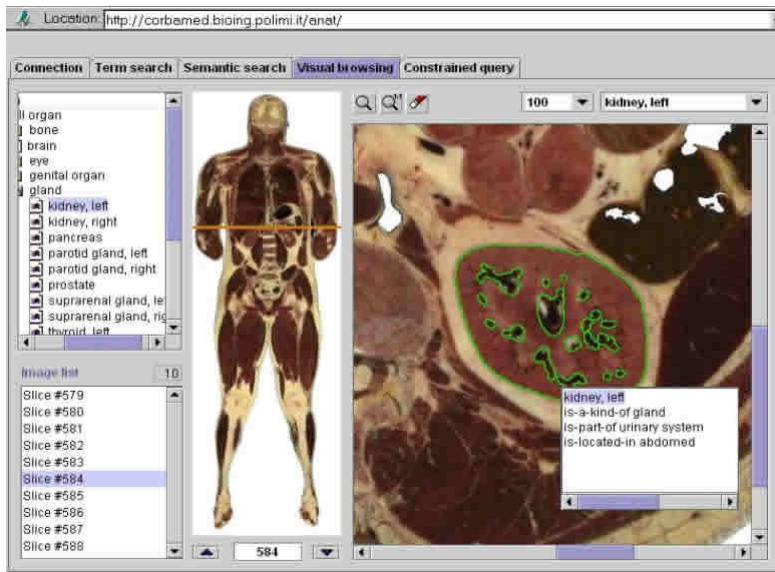
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78/86

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Virtual anatomy



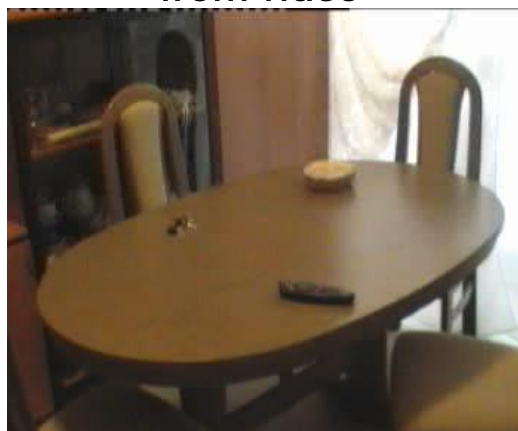
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79/86

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Augmented Reality – Camera movement from video



Applications for smart phone (Vuforia)

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80/86

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Augmented Reality through Hololens



A new vision for computing, built on a history of innovation

<https://www.microsoft.com/da-DK/hololens>

Experience in the lab



Clinical Motion Analysis

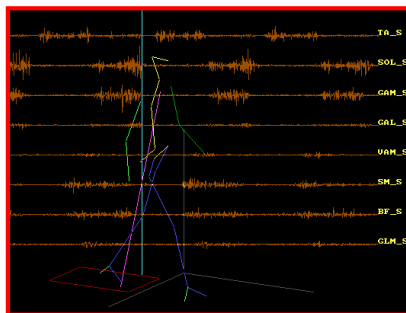


MOTION
ANALYSER

FORCE
TRANSDUCER

MATHEMATICAL
MODELS

EMG



JOINT
KINEMATICS

JOINT KINETICS

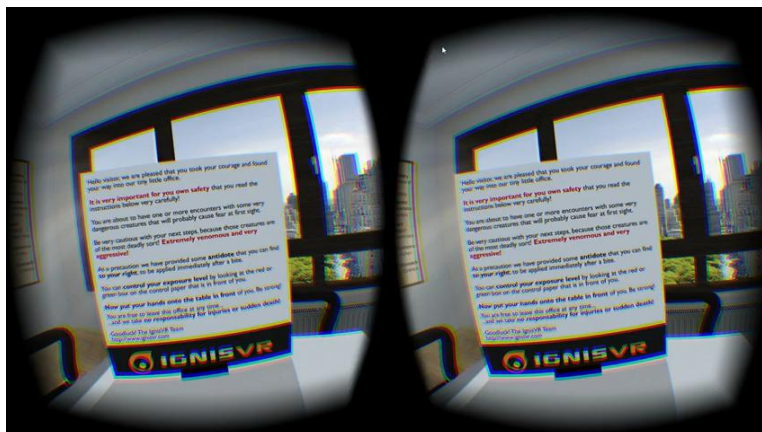
EXTERNAL
FORCES

PLANTAR
PRESSION

MUSCLE
ACTIVATION AND
FORCE



Treatment of phobias

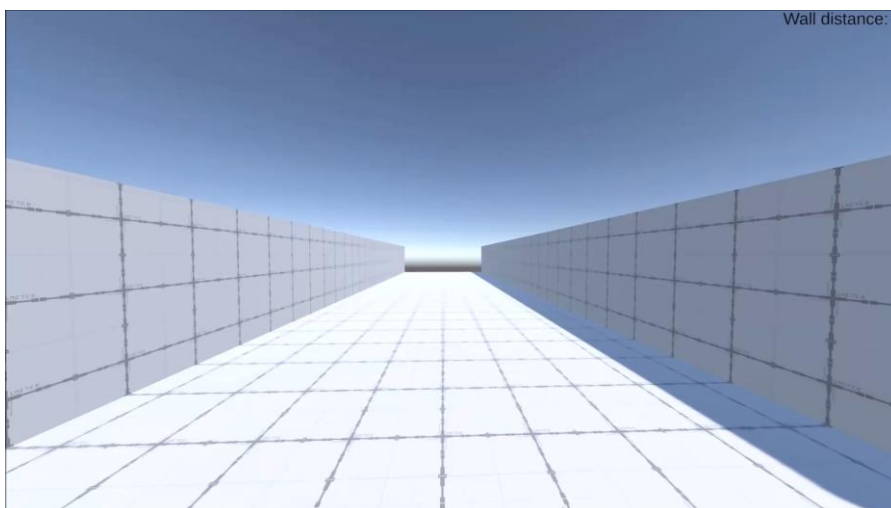


<https://store.steampowered.com/app/485270/Arachnophobia/?l=italian>

Aracnophobia, claustrophobia, agorophobia ...



Parkinson & Freezing





Virtual Tosca



Content



- Introduction
- Input Systems
- World Generators
- Virtual Reality Engine
- Output Systems
- Conclusions