Principles of Computer Game Design and Implementation

Lecture 15

We already learned

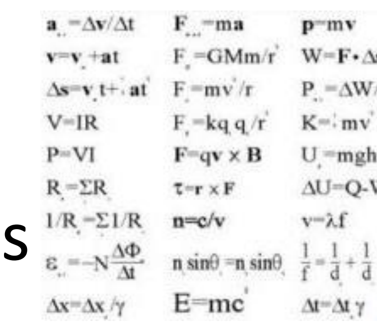
- Collision Detection
  - two approaches (overlap test, intersection test)
  - Low-level, mid-level, and high-level view

Collision Response

- What happens after a collision is detected?
  1. Prologue
     - Check if collision should be ignored
     - Sound / visual effects
  2. Collision
     - *Resolve collision*
  3. Epilogue
     - Propagate the effects
       - destroy object(s), play sound…

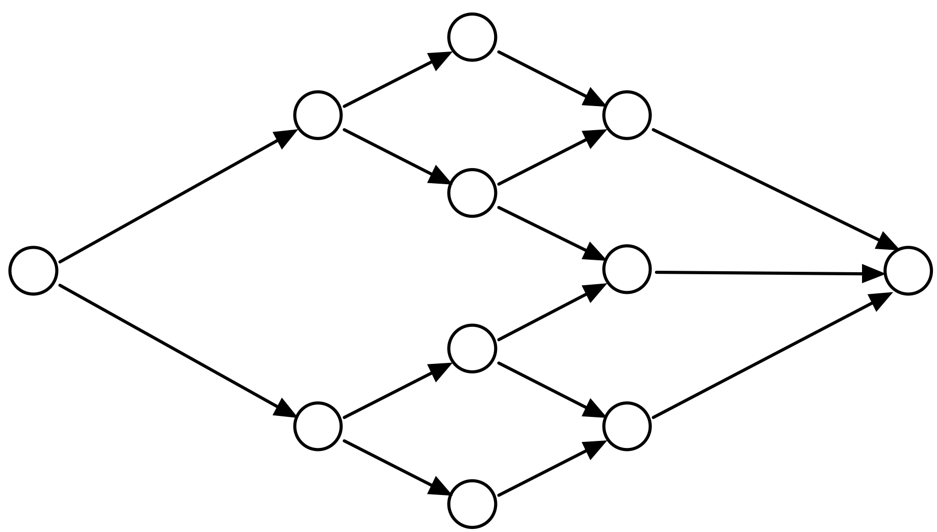
Collision Resolution

- Animation based
  - An artist models collision
    - A rocket hits a target…
  - Motion-capture
    - Sport games
- Physics based
  - Generated by an algorithm
  - Based on (more or less) realistic models



Recall: Classic Game Structure

- A convexity
- Starts with a single choice, widens to many choices, returns to a single choice

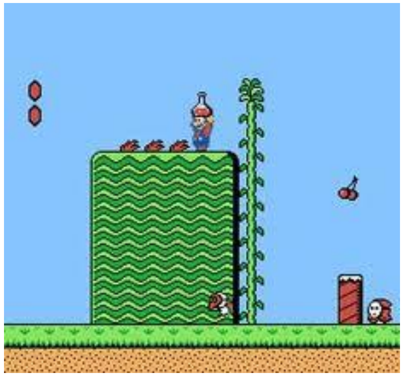


Why Physics?

- Responsive behaviour
  - Infinitely many possibilities
- For centauries people were *describing* the world
  - We can use the equations to *model* the world
- Can be hard
  - Knowledge of physics
  - “Real” physics is too expensive computationally

"Motion Science" in Games

- Kinematics
  - Motion of bodies without considering forces, friction, acceleration,…
  - Not realistic

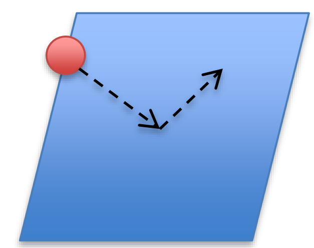


- Dynamics
  - Interaction with forces and torques

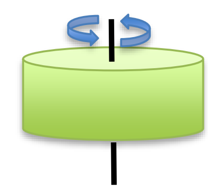
Keep It Simple

Separate translation and rotation

- Particle physics
  - A sphere with a perfect smooth, frictionless surface. No rotation
  - Interaction with forces and environment
    - Position, Velocity, Acceleration



- Solid body physics
  - Torques, angular velocity, angular momentum



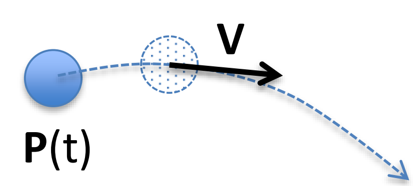
Continuous Motion

- Particles move in a "smooth way"
  - Position as a *function* of time

    P(t) is the position of P in the moment t
  - The *derivative*

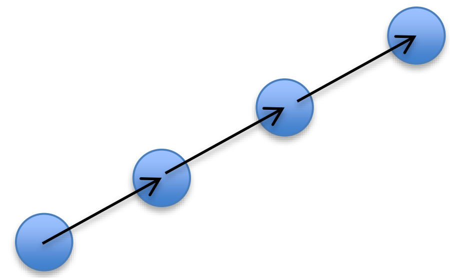
$$\frac{d\,\mathbf{P}(t)}{dt}$$

    describes how ***P***(t) changes over time
    - Velocity (speed)

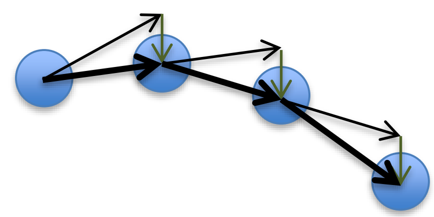


Discrete Particle Motion

- Uniform motion
  - Nothing affects the motion



- Gravitational pull



Integrators

- The process of computing the position of a body based on forces and interaction with other bodies in called *integration*

- A program that computes it is an *integrator*

Newton's Laws

1. Every body remains in a state of rest or uniform motion unless it is acted on by an external force
2. A body of mass m subject to force $\boldsymbol{F}$ accelerates as described by

Vectors

$$\boldsymbol{F} = m\boldsymbol{a}$$

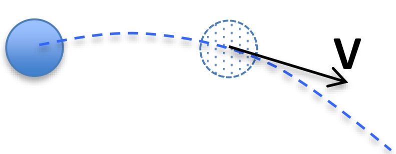
3. Every action has an equal and opposite reaction

Position and Velocity

Continuous physics

- $\mathbf{V}(t) = \dfrac{d\,\mathbf{P}(t)}{dt}$

- $\mathbf{P}(t) = \ldots$ (maths)



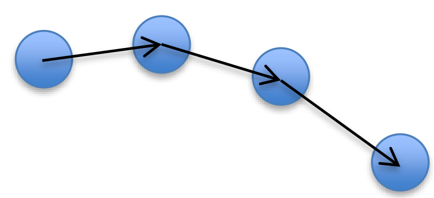
Discrete physics

- $\mathbf{V}(t) = \dfrac{\Delta\,\mathbf{P}(t)}{\Delta t} = \dfrac{\mathbf{P}_{i+1} - \mathbf{P}_i}{tpf}$

- $\mathbf{P}_{i+1} = \mathbf{P}_i + tpf \cdot \mathbf{V}(t)$

Main loop iteration

Time per frame



Recall: Arbitrary Translation

- Every iteration *update* the position

$$P = P + speed \cdot tpf \cdot \mathbf{U}(t)$$

- **U**(t) - the direction of movement
  - Depends on time!!
- *speed* is speed
- *tpf* is time per frame

Velocity and Acceleration

Continuous physics

- $$\mathbf{a}(t) = \frac{d\,\mathbf{V}(t)}{dt}$$

- $\mathbf{V}(t) = \ldots$(maths)

Discrete physics

- $$\mathbf{a}(t) = \frac{\Delta\,\mathbf{V}(t)}{\Delta t} = \frac{\mathbf{V}_{i+1} - \mathbf{V}_i}{tpf}$$

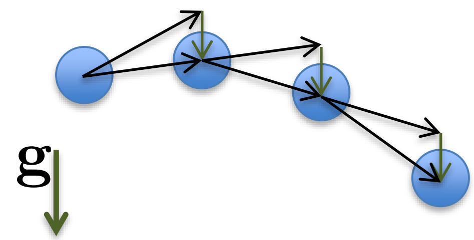
- $$\mathbf{V}_{i+1} = \mathbf{V}_i + tpf \cdot \mathbf{a}(t)$$

Main loop iteration

Time per frame

Example: Gravitational Pull

- $\mathbf{a}(t) = \mathbf{g}$ = 9.8 N/kg
- $\mathbf{V}_{i+1} = \mathbf{V}_i + tpf \cdot \mathbf{g}$
- $\mathbf{P}_{i+1} = \mathbf{P}_i + tpf \cdot \mathbf{V}_{i+1}$




```
Vector3f velocity = new Vector3f(10,10,0);
Vector3f gravity = new Vector3f(0, -9.8f, 0);
…
public void simpleUpdate() {
   velocity = velocity.add(gravity(tpf));
   ag.move(velocity.mult(tpf));
}
```

Acceleration and Force

Newton's second law: a body of mass *m* subject to force $\boldsymbol{F}$ accelerates as described by

$$\boldsymbol{F}(\mathrm{t}) = m\boldsymbol{a}(\mathrm{t})$$

$$\boldsymbol{a}(\mathrm{t}) = \boldsymbol{F}(\mathrm{t})/m$$

Use more often for simplicity

Example:

Engine thrust $\boldsymbol{F}_{\mathrm{engine}} = k\boldsymbol{U}_{\boldsymbol{V}}$

Linear drag $\boldsymbol{F}_{\mathrm{D}}(\mathrm{t}) = -b\boldsymbol{V}(\mathrm{t})$

Quadratic drag $\boldsymbol{F}_{\mathrm{QD}}(\mathrm{t}) = -\mathrm{c}|\boldsymbol{V}(\mathrm{t})|^2\boldsymbol{V}(\mathrm{t})$

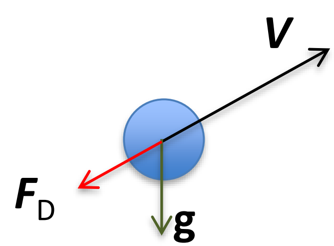
Example: Pull + Drag

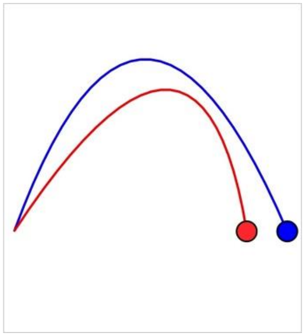
$$\mathbf{F}_{i+1} = -b\mathbf{V}_i$$

$$\mathbf{a}_{i+1} = \mathbf{g} + \mathbf{F}_{i+1}/m$$

$$\mathbf{V}_{i+1} = \mathbf{V}_i + tpf \cdot \mathbf{a}_{i+1}$$

$$\mathbf{P}_{i+1} = \mathbf{P}_i + tpf \cdot \mathbf{V}_{i+1}$$





```
Vector3f force = velocityB.mult(-b);
accelerationB = gravity.add(force.divide(m));
velocityB =
       velocityB.add(accelerationB.mult(tpf));
bg.move(velocityB.mult(tpf));
```

Example: Pull + Drag + Thrust

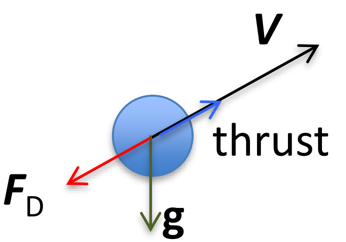
Unit vector in the direction of ***V***

$$\mathbf{F}_{i+1} = -b\mathbf{V}_i + k\mathbf{U}_{\mathbf{V}}$$

$$\mathbf{a}_{i+1} = \mathbf{g} + \mathbf{F}_{i+1}/m$$

$$\mathbf{V}_{i+1} = \mathbf{V}_i + tpf \cdot \mathbf{a}_{i+1}$$

$$\mathbf{P}_{i+1} = \mathbf{P}_i + tpf \cdot \mathbf{V}_{i+1}$$




```
Vector3f directionC = velocityC.normalize();
Vector3f forceC = velocityC.mult(-b).
                            add(directionC.mult(thrust));
accelerationC = gravity.add(forceC.divide(m));
velocityC = velocityC.add(accelerationC.mult(tpf));
cg.move(velocityC.mult(tpf));
```

Simulation Recipe

- Add up all the forces acting on the object
  - Gravity, drag, thrust, spring pull,...
- Represent the motion as discrete steps

$$\left.\begin{aligned}\mathbf{a}_{i+1} &= \mathbf{g} + \mathbf{F}_{i+1}/m \\ \mathbf{V}_{i+1} &= \mathbf{V}_i + tpf \cdot \mathbf{a}_{i+1} \\ \mathbf{P}_{i+1} &= \mathbf{P}_i + tpf \cdot \mathbf{V}_{i+1}\end{aligned}\right\}\ \text{Euler steps}$$

Rotation

- Rotation of a uniform (again simplification) solid body can be described mathematically
  - Speed vs angular speed
  - Force vs torque
- Represent as discrete motion
- Use Euler steps to compute the rotation matrix
- Combine with translation

Hard but doable

Accuracy of Simulation

- How accurate this simulation is?
- Does it matter?
  - It’s all about illusion, if the behaviour looks right, we do not care.
- But…