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Abstract

Geometric modeling systems allow users to create, store, and manipulate models of three-dimensional (3-D) solid objects. These geometric modeling systems have found many applications in CAD/CAM and robotics areas. Graphic display capability which rivals photographic techniques allows realistic visualization of design and simulation. Capabilities to compute spatial and physical properties of objects, such as mass property calculation and static interference check, are used in the design and analysis of mechanical parts and assembly. Output from the geometric modelers can be used for automatic programming of NC machines and robots.

These geometric modeling systems are powerful in many application domains, but have severe limitations to be used for tasks such as model-based computer vision. Among others,

1. There is no explicit symbolic representation of the two-dimensional (2-D) information obtained by the projection of the 3-D model. The output image displayed on the screen is a set of pixel intensity values, with no knowledge of the logical grouping of points, lines and polygons. Also, the relationship between 3-D and 2-D information is not maintained properly.

2. Most of the current 3-D geometric modeling systems are designed with a closed architecture, with a minimum of documentation describing the internal data structures. Moreover, some of the data structures are packed into bit-fields, making understanding and modification difficult.

3. They run as stand-alone interactive systems and cannot easily be interfaced to other programs.

To address these shortcomings, we have developed the VANTAGE geometric modeling system. VANTAGE uses a consistent object space representation in both the 3-D and 2-D domains, which makes it suitable for computer vision and other advanced robotics applications. Its open architecture design allows for easy modification and interface to other software. This paper discusses the design goals and methodology for the VANTAGE geometric modeler.
1. Introduction

Geometric modeling systems allow users to create, store, and manipulate models of three-dimensional (3-D) solid objects. These geometric modeling systems have found many applications in CAD/CAM and robotics areas. Although powerful in many application domains, there are some limitations of these geometric modeling systems, which make them difficult to be used for tasks such as model-based computer vision. Among others,

1. There is no explicit symbolic representation of the two-dimensional (2-D) information obtained by the projection of the 3-D model. The image data is a set of pixel intensity values, with no knowledge of the logical grouping of points, lines and polygons.

2. They are designed with a closed architecture, with a minimum of documentation describing the internal data structures. Worse, some of the data structures are packed into bit-fields, making understanding and modification difficult.

3. They run as stand-alone interactive systems and cannot easily be interfaced to other programs.

To address these shortcomings, we have developed the VANTAGE geometric modeling system. VANTAGE uses a consistent object space representation in both the 3-D and 2-D domains, which makes it suitable for computer vision and other advanced robotics applications. Its open architecture design allows for easy modification and interface to other software. The problems involving model based vision are the main driving force behind this work and VANTAGE has applications in computer vision and advanced robotics research.

The current version of VANTAGE is reasonably debugged and has decent graphic routines and user interface. This manual covers the following areas:

- General concepts and terminology
- Overview of design and implementation
- Primitive solids and coordinate transformations
- Operations on solids
- 3-D boundary representation
- Light-sources, cameras
- Scenes and 3-D properties
- Images and 2-D properties

VANTAGE is currently supported on SUN running Lucid Common Lisp or Allegro Common Lisp. Most of the code is portable to other lisp environments except for the graphic and user-interface routines. VANTAGE can also run under X-Window system. Please direct all enquiries to vantage@cs.cmu.edu.
2. Terminology

- **Primitives:** The basic solids provided by the system. They can be defined by giving required dimensions. The primitives are cube, cone, truncated-cone, cylinder, sphere, 2.5prism, 2.5cone, triangular-prism and right-angle-prism.

- **Boolean Operations:** The operations allowed on the solids to move, modify or create a resulting solid. The operations defined are union, intersection and difference.

- **CSG-Definition:** The definition of solids is stored in the form of a tree structure. The leaf nodes are either primitives or nil. A parent node corresponds to a boolean operation applied to its corresponding children nodes. When creating the boundary representation for a particular node, the boundary representation for all the children of the node is also created recursively.

- **Boundary representation:** A solid is represented as a collection of faces, a face as a collection of edges, and an edge is defined by its two end vertices. The vertices are defined by their x, y and z coordinates. Topological information is included in the form of winged-edge representation.

- **Winged-edge representation:** A way of defining the topological relationship. There are eight slots for each edge which define the two end vertices (P-vertex, N-vertex), four neighboring edges (PCW, PCCW, NCW, NCCW) and two adjacent-faces (P-face, N-face).

- **3D-hierarchical structure:** In the boundary representation the cylindrical, conical and spherical faces are approximated by a finite number (user specified) of planar faces. After any sequence of boolean operations the faces derived from a same primitive surface are grouped so that they can be treated as a single entity. Also there is provision to group faces that are tangent to each other across a common edge.
3. VANTAGE - Concepts and Design

3.1. Motivations for Developing VANTAGE

Currently available geometric modeling systems have critical limitations to be used in applications which require flexible, explicit, and user-specified access, attachment, and modification of the information within the systems. For example, developing a model-based vision system based on an object model requires analyzing how the object features, such as faces, edges, etc., will appear as the camera positions vary. However, though the graphic display of the object generates beautiful "images", usually no explicit symbolic representations of the two-dimensional information are computed in the projection of a 3-D object model. The graphical output image is a set of pixel intensity or color values, with no knowledge of the logical grouping of points, lines, and polygons, or pointers to the original object features. Humans can interpret the image, but the explicit information that a vision program may require is not available.

Rarely do the built-in functions of a geometric modeling system satisfy all the representational and computational capabilities that a user needs for his own new application. Theoretically, writing or modifying a few modules to access and manipulate the information hidden in the system or adding a few representational capabilities to the existing ones will bring about the required capabilities. In practice, however, such modifications and additions are very difficult and painful, if not impossible. Most systems are designed with a closed architecture, with a minimum of documentation describing the internal data structures. Worse, due to their implementation in such languages as Fortran, many of the data structures are packed into bit-fields, making understanding and modification above a certain level of sophistication impractical.

Recognizing these limitations of currently available geometric modeling systems, we have decided to develop a new flexible geometric modeler, VANTAGE, so that:

- Both 3-D and 2-D information of objects can be explicitly represented by symbolic data structures.
- A user can easily modify the system, add new capabilities, and interface his programs to it.

Our primary application of VANTAGE will be in the area of model-based computer vision, but we expect the flexibility and modifiability of VANTAGE will allow it to be used as a tool for many other
advanced robotics applications.

3.2. Open Architecture
Many existing modelers act as a black box for the application programs and discourage sharing data. The approach we take emphasizes direct interaction between the modeling system and the application program. The collection of all data items, such as surface, edge, camera, light-source, etc., describing objects and their relationships form the geometric database. The geometric engine, consisting of both the system-defined and user-defined functions, can access and manipulate it. This implies that all the system and application programs are at the same level of hierarchy in terms of accessing information, with minimal distinction between them. Figure 3-1 illustrates the open architecture.

![Geometric Data](image)

**Figure 3-1:** Open Architecture of VANTAGE

3.3. Lisp and frame-based Representation
VANTAGE avoids complex and heterogeneous data structures. All data in VANTAGE are represented in a standardized manner by the use of frames. Frames are analogous to schema or concepts as defined in other knowledge representation languages. A frame is composed of slots, facets and fillers. For example, a frame structure defining a face may look like:

```lisp
(BOTTOM-FACE
  (is-a 3-D-face))
(area
  (value 140)
  (if-added (update-max-area-face)))
(face-of
```
In this example, **BOTTOM-FACE** is the name of the frame. The slots are used to represent various attributes of a frame, such as **is-a**, **area**, **face-of**, and **edge-list**. A slot can have multiple facets such as **value** and **if-added**. **3-D-face**, **140**, **update-max-area-face** are fillers defining contents of different facets. **Frames** are like record structures in conventional programming languages, but have much more flexibility and features. Frames, slots, facets, and fillers can be added or erased at any time. Frames also provide a mechanism to automatically select and execute procedures and functions attached to a frame depending on the operation performed on a particular slot. These functions are called **demos**. In the above example, **update-max-area-face** is a demon which is fired automatically to update, if necessary, the variable **maximum-area-face** when a value for the slot **area** is added. The frame structure is omnipresent throughout the system. The flexibility of frames provides an effective means to allow smooth interface to user supplied programs. VANTAGE is implemented in the **COMMON LISP** language. LISP combines symbolic processing with features from traditional computing. By writing VANTAGE in LISP, it inherits all the merits of the LISP language such as interaction, incremental building, symbolic representation etc. We believe that VANTAGE will have successful applications in the A.I. world.

### 3.4. Solid and Boundary Representation

We have selected the Constructive Solid Geometry approach for representing the shapes of objects in VANTAGE. VANTAGE provides basic solid primitives like cube, cylinder, etc. The user creates new solids by making boolean operations (union, difference and intersection) on these primitives. A 3-D boundary representation of each object is maintained within the system. This contains lists of faces, edges and vertices. Vertices contain their respective coordinate values, and edges join these vertices. The faces are planar polyhedra and represented by a collection of connected edges. The neighborhood information or topology relates the edges, faces and vertices of the solid. This information in VANTAGE is stored in the form of winged-edge representation. An edge has two end vertices, four neighboring edges and two faces defining a strict relationship.
3.5. Relations Between 2-D and 3-D

A model-based vision system attempts to recognize objects in images by matching features in the image with those expected from the model of the scene. Many current geometric modelers are good at synthesizing images of a scene with a given viewing position and lighting condition. It is, however, very difficult to extract symbolic representations of expected appearances of the object so that they can be used in designing recognition strategies. One of the VANTAGE design goals is to provide a capability to explicitly represent the relationships between 3-D information (such as shape, surface, and lighting) in the scene and 2-D information (such as visibility, shadow, and projected shape) in the image.

For a particular viewing condition, the 3-D faces are projected on the viewing plane and the visible portion of the projections result in 2-D face-regions. These 2-D face-regions are a collection of 2-D arcs and the 2-D arcs connect 2-D joints. The hierarchy of 2-D face-regions, 2-D arcs and 2-D joints is the same as faces, edges and vertices at the 3-D level.

Image formation in general is dictated by the physical properties of the considered surfaces. A 3-D face contains some slots for representing various properties like color, surface-roughness, shadows, etc. They are classified according to the cause. For example, a particular 3-D face can have shadows due to different light sources such as light-source-a and light-source-b. All these shadow conditions interact to produce the final image. The 3-D face properties are projected on the 2-D regions, which are divided into property-regions.

<table>
<thead>
<tr>
<th>3-D level</th>
<th>2-D level</th>
</tr>
</thead>
<tbody>
<tr>
<td>3-D face</td>
<td>2-D region</td>
</tr>
<tr>
<td>3-D edge</td>
<td>2-D arc</td>
</tr>
<tr>
<td>3-D vertex</td>
<td>2-D joint</td>
</tr>
<tr>
<td>3-D property</td>
<td>2-D property-region</td>
</tr>
</tbody>
</table>

**Table 3-1: Relation between 3-D and 2-D level**

Table 3-1 explains the relation between the two levels. The information at the 2-D and 3-D levels have a correspondence and can be referenced back and forth. In addition, VANTAGE maintains topological information not only at the 3-D level but also at the 2-D level.
3.6. Organization

Figure 3-2 shows the overall organization of VANTAGE.

1. The user creates a solid by applying operations on primitives solids. The definition of the solid is stored in a Constructive Solid Geometry (CSG) Tree.

2. The 3-D boundary representation of the solid is generated from the CSG tree in the 3D geometric database. The face properties (e.g. color, shadow, and visibility) are also maintained in the 3D geometric database.

3. The user defines a 3-D Scene that contains a collection of solids, environmental conditions (e.g. lighting conditions), and a viewing condition.

4. The 3-D scene is projected to generate a 2-D Image, for which VANTAGE creates a complete explicit representation (2-D boundary representation and 2-D Properties), which contains geometric and topological information for all visible regions, as well as back-pointers to the 3-D boundary representation in the 2D geometric database.

The subsequent sections detail the different parts of the system.

3.6.1. Solid Definition

In Constructive Solid Geometry, an object is generated by applying successive operations (union, intersection, difference, move, mirror) on a set of primitive solids (cube, cylinder, cone, sphere). A CSG tree represents internally this CSG definition. A leaf node of a CSG tree defines a primitive solid. An intermediate node specifies an operation to be performed on its descendants, and corresponds to the solid resulting from the operation. Figure 3-3 shows an example of a CSG tree.
3.6.2. 3-D Boundary Representation

A 3-D boundary representation of each object is maintained within the system. It consists of a four level hierarchy of frames: body, face, edge, and vertex. A body is made of faces, a face is defined by its edges, and an edge has two end vertices. Each element contains some geometric properties (coordinates of the vertices, equations of the faces, position of the body in space). In addition, VANTAGE maintains a complete representation of topological relationships in the form of a winged-edge representation that lists the end vertices, neighboring edges and faces of every edge (see figure 3-4).

Although VANTAGE includes non-polyhedral primitives such as cylinders and cones, all non-planar surfaces (cylindrical, conical or spherical surfaces) are approximated by a finite number of planar faces. In the same way, all curves are represented by a collection of linear edges. The number of planar faces used to represent a non-planar surface is entered by the user.

VANTAGE stores the exact geometric definition of each surface and curve as a separate frame. VANTAGE also maintains a pointer from every planar face that approximates a non-planar surface to the corresponding surface, and similarly from the approximating edges to the corresponding curves.
The surface/curve frames are used for grouping faces/edges that approximate the same surface/curve. Also, any operation that requires the exact geometric definition of surfaces and curves (e.g., generation of parametric equations) can be performed using the surface and curve frames.

VANTAGE builds two more levels of representation based on surface properties. Figure 3-5 illustrates the grouping and merging operations for this purpose. First, using references to the surface frames, VANTAGE can group a set of adjacent planar faces that approximate the same curved surface into a curved face frame. Similarly, connected linear edges that approximate the same curve are also grouped into a curved edge frame. Second, faces that are tangent across an edge, that is, C1 continuous, are also merged into one. Since detecting the C1 continuity is sometimes ambiguous due to the finite precision of floating point calculation, VANTAGE provides an interactive graphic interface that allows the user to select any pair of adjacent faces he desires to merge.
Importantly, the topological relationships of grouped and merged surfaces are also maintained in a winged-edge representation. This feature is very useful for computer vision applications, where a continuous surface must often be treated as a single surface.

3.6.3. 3-D Face Properties

Property descriptions of the faces of solids can be attached to the 3-D boundary representation. There are two types of face properties:

- Physical properties inherent to the solid itself (e.g. color, texture).
- Properties that result from the environment of the solid (e.g. cast shadow for a given light-source). These properties are computed at the time of projection.

![Figure 3-6: 3-D Face Properties for a Light-source](image)

Figure 3-6 illustrates the 3-D property representations in the case of color and shadow. These divisions due to different properties are stored in the property frame of the 3-D faces. They are also classified according to the cause. For example, a particular 3-D face can have shadows due to different light-sources such as light-source-a and light-source-b.

3.6.4. 3-D Scene

A 3-D scene is a portion of the world for which we can create an image. It is composed of:

- A collection of solids
- A selection of physical properties of the solids (e.g. color).
- A set of environmental conditions, that can include:
  - A set of light-sources (one or several).
A sensor, which is used to generate a 2-D image of the scene (e.g. a camera).

Each scene condition (e.g. a light-source) is defined as a separate frame containing all necessary information: location, color of light, point/extended light-source, sensor characteristics, etc.

3.6.5. 2-D Image

The 2-D representation of a 3-D scene is an explicit symbolic representation of the image that is obtained by projecting the scene using the specified sensor (see Figure 3-7). VANTAGE provides a capability to explicitly represent the relationships between 3-D information (such as shape, surface, and lighting) in the scene and 2-D information (such as visibility, shadow, and projected shape) in the image. For a particular viewing condition, the 3-D faces are projected on the viewing plane and the visible portion of the projections result in 2-D face-regions. These 2-D face-regions are a collection of 2-D arcs and the 2-D arcs connect 2-D joints. The hierarchy of 2-D face-regions, 2-D arcs and 2-D joints is the same as faces, edges and vertices at the 3-D level.

![Figure 3-7: Projection of a 3-D scene, and regions of the resulting image.](image)

The algorithm to project a scene from 3-D to 2-D in addition generates all topological relationships among the face-regions (projections of the 3-D faces) of the image something similar to that of the 3-D level.
3.6.6. 2-D Property Regions

Different lighting conditions interact to produce the final image. To compute whether a face is illuminated by a light-source or shadowed, we take advantage of the correspondence between a light-source and a sensor, as shown in table 3-2. When projecting a scene using a light-source as viewpoint, the 2-D regions obtained represent the illuminated/cast-shadowed parts of the scene. These 2-D regions are back-projected on the 3-D faces of the solids, and stored as the 3-D face properties associated with the light-source. These 3-D face properties are projected on the 2-D face-regions, which are divided into property-regions.

<table>
<thead>
<tr>
<th>Shading</th>
<th>Visibility</th>
</tr>
</thead>
<tbody>
<tr>
<td>illuminated</td>
<td>visible</td>
</tr>
<tr>
<td>cast-shadowed</td>
<td>occluded</td>
</tr>
<tr>
<td>self-shadowed</td>
<td>back-face</td>
</tr>
</tbody>
</table>

Table 3-2: Light-source/Sensor

"Painted" Image

Figure 3-8: Property regions associated to a light-source

Figure 3-8 explains the property-regions, which are 2-D face properties of the 2-D face regions.
4. Invoking the system

The Lisp system should be invoked first. VANTAGE currently runs under LUCID and ALLEGRO common lisp environments. Then load the file "/usr/vantage/vantage-init.lisp". This will initialize the VANTAGE system.

```lisp
> (load "/usr/vantage/vantage-init.lisp")

VANTAGE SOLID MODELING SYSTEM V1.0
VISION AND AUTONOMOUS SYSTEMS CENTER
THE ROBOTICS INSTITUTE

Loading Subsystem - Framekit
- Solids
- Windows
- Utilities

Here you go............
Send Comments and Bug reports to vantage@cs.cmu.edu

```

At the end it will open up a new graphic screen called "LISP-Screen". Inside there will be a default window named "vantage window". By clicking the left mouse button inside the window, a pop-up-menu interface can be invoked. Users interested in creating otherwidows on the Lisp screen are encouraged to go through the Chapter 12 of the "SUN Common Lisp User’s Manual" titled "WINDOW TOOL KIT".
5. CSG Definition of a Solid

The creation of a CSG-node is performed by the macro \texttt{csgnode}. This macro allows the creation of primitive solids or the creation of solids by applying boolean operations on existing solids.

The following macro creates a solid:

\begin{verbatim}
(csgnode solid-name type parameters)
\end{verbatim}

where \texttt{type} can be either a \texttt{primitive-type} (e.g. \texttt{cube}, \texttt{cylinder}, etc.), or an operation (e.g. \texttt{union}, \texttt{move}, etc.). The \texttt{csgnode} command can also take optional arguments that are defined below.

5.1. Primitives

They are defined by the macro:

\begin{verbatim}
(CSGNODE solid-name primitive-type parameters &key (trans *identity*))
\end{verbatim}

or the function:

\begin{verbatim}
(CSGNODE* solid-name primitive-type parameters &key (trans *identity*))
\end{verbatim}

\texttt{CSGNODE*} is like \texttt{CSGNODE}, except that it evaluates its arguments.

\textit{primitive-type} is one of the following types:

- \texttt{cube}
- \texttt{cylinder}
- \texttt{cone}
- \texttt{truncated-cone}
- \texttt{sphere}
- \texttt{iso-prism}
- \texttt{right-angle-prism}
- \texttt{2.5-prism}
- \texttt{2.5-cone}

or their abbreviated forms:

- \texttt{cu}
- \texttt{cub}
- \texttt{cy}
- \texttt{cyl}
- \texttt{co}
- \texttt{con}
- \texttt{tr}
- \texttt{sph}
- \texttt{iso}
- \texttt{rt}
- \texttt{2.5p}
- \texttt{2.5c}

\textit{parameters} is a list of numbers and depends on the primitive type.

- \texttt{cube} \hspace{1cm} \texttt{(x-length y-length z-length )}
- \texttt{cylinder} \hspace{1cm} \texttt{(radius height number-of-app-faces )}
- \texttt{cone} \hspace{1cm} \texttt{(radius height number-of-app-faces )}
- \texttt{truncated-cone} \hspace{1cm} \texttt{(bottom-radius top-radius height number-of-app-faces )}
- \texttt{sphere} \hspace{1cm} \texttt{(radius approximation-number )}
• iso-prism \((base\ side\ height)\)
• right-angle-prism \((side1\ side2\ height)\)
• 2.5-prism \(\text{height}\ (x_1\ y_1)\ (x_2\ y_2)\ (\ldots)\)
• 2.5-cone \(\text{height}\ (x_{\text{base}}\ y_{\text{base}})\ (x_1\ y_1)\ (x_2\ y_2)\ (\ldots)\)

\(trans\) is an optional parameter that defaults to the identity transformation. It specifies the rigid-motion attached to the node. It can be one of the following:

- **name**: name of an already defined rigid-motion.
- list of six float-numbers \((x\ y\ z\ roll\ pitch\ yaw)\); the system will generate a motion matrix and will give a new name for it. The angles roll, pitch, and yaw can be entered in degrees or radians depending on the current value of the variable *angle-mode* (see page 29).
- list \((name\ x\ y\ z\ roll\ pitch\ yaw)\); same as above but the given name is assigned.

See Appendix A for an example of each primitive.

### 5.2. Rigid-Motion

#### 5.2.1. Moving a solid

(CCSGNODE solid-name move solid &key (trans *identity*) (fast NIL))

Defines a new solid obtained by applying to an existing solid the transformation specified by \(trans\).

\(trans\) is as defined in the previous section.

\(fast\) specifies whether the boundary representation of the child nodes should be destructively affected or not, when generating the boundary representation for the specified node. \(fast\) takes one of the following values:

- **NIL**: the boundary representation of the child nodes will be copied and not destructed when generating the boundary representation of the specified node.
- **T**: the boundary representation of the child nodes will be destructed when generating the boundary representation of the specified node. They will not be copied, therefore saving computation time.
- **all**: all nodes below the specified node in the CSG-tree will have their \(fast\) flag set to **T**. Only the boundary representation of the specified node will remain.

(CCSGNODE* solid-name move solid &key (trans *identity*) (fast NIL))

CSGNODE* is like CSGNODE, except that it evaluates its arguments.

(MOVE-CSG-NODE node-name trans)
Moves an existing solid by applying to it the rigid-motion transformation specified by $trans$. The user is asked to confirm the move command when a boundary-representation exists for the node or when the node has parent nodes. If the user chooses to move the node anyway, the boundary-representations of the node and its possible parents are deleted. Note that from now on, the parents of the moved node will take into account the new location of the node.

$\text{(MOVE-CSG-NODE* node-name trans)}$

MOVE-CSG-NODE* is like MOVE-CSG-NODE, except that it evaluates its arguments.

### 5.2.2. Defining a transformation

A rigid-motion can be defined at the time it is used, as explained above, or using one of the following functions:

$\text{(MK-MOTION-MATRIX (name x y z roll pitch yaw))}$

$x$, $y$, $z$ define the position of the new origin, and $roll$, $pitch$, $yaw$ define the rotations to perform about the initial $z$, $y$ and $x$ axis. If $name$ is absent a system-generated name will be assigned.

$\text{(MK-ROTATION &key (name (nil)) (rpy '(0 0 0)) (axis-angle (nil)) (center '(0 0 0)))}$

Creates a rotation transformation, defined by the center of rotation, and either the roll, pitch and $yaw$ coefficients, or the rotation axis vector plus the rotation angle. If $name$ is absent a system-generated name will be assigned.

$\text{(MK-ROTATION* &key (name nil) (rpy '(0 0 0)) (axis-angle nil) (center '(0 0 0)))}$

MK-ROTATION* is like MK-ROTATION, except that it evaluates its arguments.

$\text{(MK-TRANSLATION &key (name nil) (xyz '(0 0 0)))}$

Creates a translation transformation, defined by the translation vector. If $name$ is absent a system-generated name will be assigned.

$\text{(MK-TRANSLATION* &key (name nil) (xyz '(0 0 0)))}$

MK-TRANSLATION* is like MK-TRANSLATION, except that it evaluates its arguments.
(MK-COMBINED-TRANSFORMATION &key (name NIL) (trans-list nil))

Creates a transformation resulting from several successive transformations. trans-list is the list of transformations to combine. The matrix of the new transformation is the product, from left to right, of the matrices of the transformations of trans-list. If name is absent, a system-generated name will be assigned.

(MK-COMBINED-TRANSFORMATION* &key (name NIL) (trans-list nil))

MK-COMBINED-TRANSFORMATION* is like MK-COMBINED-TRANSFORMATION, except that it evaluates its arguments.

5.3. Boolean Operations

Complex solids are created by applying boolean operations on other solids.

(CSGNODE solid-name boolean-operation solids &key (trans *identity*) (fast NIL))

A new solid is generated by applying the specified operation to the specified solid(s), and then by transforming the resulting solid by the specified rigid-motion.

boolean operation is one of the following operations:

- union
- difference
- intersection
- inverse

or their abbreviated form:

- un
- uni
- di
- dif
- int
- inv

solids is a list of two solids, except for the inverse operation, in which case it is just one solid.

trans is specified as explained in the previous section.

fast is explained in the previous section.

(CSGNODE* solid-name boolean-operation solids &key (trans *identity*) (fast NIL))

CSGNODE* is like CSGNODE, except that it evaluates its arguments.

Example:

The following commands create the nodes that appear in the CSG-tree of Figure 3-3.
5.4. Mirror Operation

This operation creates the symmetric solid of a specified solid relatively to a specified plane.

(CSGNODE solid-name mirror parameters &key (trans *identity*) (fast NIL))

parameters is a list (solid normal-x normal-y normal-z distance) specifying the solid and the mirror-plane. The plane is defined by the x,y,z coordinates of its normal vector, and by its orthogonal distance to the origin.

(CSGNODE* solid-name mirror parameters &key (trans *identity*) (fast NIL))

CSGNODE* is like CSGNODE, except that it evaluates its arguments.

5.5. Redefining and Deleting solids

The definition of a node can be changed or deleted. If the affected node has ancestor nodes, then they are all affected as well. When defining a solid using csgnode, if the specified name is already used, then VANTAGE asks if it should use another name or replace the existing solid by the new one.

(DELETE-CSG-NODE node-name)

Deletes the node node-name and its boundary-representation (if it exists). Also deletes the parent csg-nodes of the node (if any), after confirmation from the user.
5.6. Information on the CSG-Tree

The CSG-Tree specifies how the solids are created, and stores all the node operations in a tree structure. Each node will correspond to a 3D-solid. The leaf nodes are primitive solids. The other nodes are obtained by applying an operation on its child nodes.

(DELETE-CSG-NODE* node-name)

DELETE-CSG-NODE* is like DELETE-CSG-NODE, except that it evaluates its argument.

(CSG-TREE)

Prints out information on the existing CSG-nodes.

(DESCRIBE-CSG-NODE node-name)

Prints out all the operations involved in the creation of the solid corresponding to node-name.

(DESCRIBE-CSG-NODE* node-name)

DESCRIBE-CSG-NODE* is like DESCRIBE-CSG-NODE, except that it evaluates its arguments.

(DESCRIBE-CSG-NODES)

Calls the function describe-csg-node for all the nodes.

(DESCRIBE-CSG-NODES* node-name)

DESCRIBE-CSG-NODES* is like DESCRIBE-CSG-NODES, except that it evaluates its arguments.
6. Boundary Representation

This chapter describes the functions that generate the boundary-representation of a solid.

**(BOUN-REP node-name)**

Creates a complete 3d boundary-representation for the solid defined by the node. This representation consists of frames that represent the vertices, the edges, the faces, and the body (the name of the body-frame is node-name (with suffix 'z')). If a boundary-representation already exists for the node, nothing is done.

A boundary-representation is generated for all nodes starting with the leaf-nodes (primitive solids) and going up the csg-tree until the specified node. All intermediate nodes that do not have a boundary-representation yet get one in the process, except those whose parent-node has the fast flag on, which get only a temporary boundary-representation that is destructively modified in the process and deleted. If a node already has a boundary representation, the existing representation is used for that node and VANTAGE does not generate a boundary-representation for the node and its child-nodes.

**(BOUN-REP* node-name)**

BOUN-REP* is like BOUN-REP, except that it evaluates its arguments.

**(3D-STRUCTURE node-name)**

It has the same effect as boun-rep, but in addition the solid gets a 3D-Hierarchical structure (grouping of faces approximating a same primitive surface...). If a boundary-representation already exists for the node, only the grouping of faces and edges is performed. If the grouping operations have also already been done, the function does not do anything.

**(3D-STRUCTURE* node-name)**

3D-STRUCTURE* is like 3D-STRUCTURE, except that it evaluates its arguments.

**(3D node-name)**

Merges connected faces that are specified by the user. The new faces that are created are at the
top-level in the hierarchy of faces (see Figure 3-5). If a boundary-representation has not been
generated yet, boun-rep is first called.

This main application of this function is to merge connected faces that have a continuous normal
across the connecting edge. Since VANTAGE approximates all the higher order surfaces by planar
polyhedra it is impossible to automatically detect those edges across which the merge should take
place. So it requires interaction from the user through mouse input.

For merging some faces, some small faces may have to be created at the boundary of a surface, due
to the approximation of the surface. Such configurations are first detected, and the user is asked to
confirm any modification. Then the user can enter the faces he wants to merge. Any selected face is
then considered as an approximated face and grouped with its neighbors to create the parent faces.

(3D* node-name )

3D* is like 3D, except that it evaluates its arguments.

The boundary-representation of a node can be deleted using:

(DELETE-BOUN-REP node-name )

Deletes the boundary-representation of the node node-name (if it exists), with all its vertices, edges,
faces.

(DELETE-BOUN-REP* node-name )

DELETE-BOUN-REP* is like DELETE-BOUN-REP, except that it evaluates its argument.
7. Sensors

The definition of sensor applies to cameras and light-sources. In can also include combinations of cameras and light-sources (sensor-components) using AND and OR operations.

(CAMERA name location key (target '(0 0 0)) (focal nil) (limit-angle nil))

Creates a camera that is positioned at location \((x\ y\ z)\) and that points toward target, with the specified focal-length.

\(\text{limit-angle}\) is the maximum angle (in degrees) between the normal of a face and the viewing direction, for which the face is visible. The default \(\text{NIL}\) value for \(\text{limit-angle}\) corresponds to a limit-angle of 90 degrees.

(CAMERA* name location key (target '(0 0 0)) (focal nil) (limit-angle NIL))

CAMERA* is like CAMERA, except that it evaluates its arguments.

(LIGHT-SOURCE name location key (target '(0 0 0)) (focal nil) (limit-angle NIL))

Creates a light-source that is positioned at location \((x\ y\ z)\) and that points toward target, with the specified focal-length.

\(\text{limit-angle}\) is the maximum angle (in degrees) between the normal of a face and the lighting direction, for which the face is lit. The default \(\text{NIL}\) value for \(\text{limit-angle}\) corresponds to a limit-angle of 90 degrees.

(LIGHT-SOURCE* name location key (target '(0 0 0)) (focal nil) (limit-angle NIL))

LIGHT-SOURCE* is like LIGHT-SOURCE, except that it evaluates its arguments.

(MAKE-SENSOR-COMPONENT name type params key (focal NIL) (limit-angle NIL))

Creates a camera or a light-source with the given parameters.

\(\text{type}\) is either camera or light.

\(\text{params}\) is a list of six numbers describing \(x,\ y,\ z,\ \text{roll},\ \text{pitch}\) and \(\text{yaw}\). The camera points towards the negative \(z\)-axis given by the camera-coordinate system defined by the parameters.

\(\text{focal}\) specifies the focal distance of the perspective projection, or, when equal to \(\text{NIL}\), characterizes an orthographic projection.
limit-angle is the maximum angle (in degrees) between the normal of a face and the projection direction, for which the face is lit. The default NIL value for limit-angle corresponds to a limit-angle of 90 degrees.

(ROTATE-CAMERA-AROUND-AXIS camera angle )
Rotates a camera around its viewing direction. The angle unit is given by *angle-mode*.

(ROTATE-CAMERA-AROUND-AXIS* camera angle )
ROTATE-CAMERA-AROUND-AXIS* is like ROTATE-CAMERA-AROUND-AXIS, except that it evaluates its arguments.
8. Scene and 3-D Properties

8.1. Scene

The following functions define a 3-D scene. The environmental properties applied to the scene (lighting conditions) are added to the definition of the scene at the time of calculation of the 3-D property regions of the scene for given light-sources (see section 8.2 and the IMAGE function, page 26).

(SCENE name csg-node-list)  
Defines a 3d-scene by a list of csg-nodes. A boundary-representation of all the bodies of the scene should exist before creating the scene.

(SCENE* name 3d-body-list)  
SCENE* is like SCENE, except that it evaluates its arguments.

8.2. 3-D Properties

(PROJECT-AND-BACK-PROJECT scene sensor optional (merge-shadows T) )  
Generates the 3-D properties of the specified scene for a given sensor (camera or light-source). A process of projection and back-projection is performed, as explained in paragraph 3.6.6, page 12. When the sensor is a camera, the regions generated on the 3-D faces of the scene are the visible, occluded, or back-oriented areas of the scene for the given camera. For a light-source, the illuminated, cast-shadowed and self-shadowed areas of the scene are obtained (see table 3-2). The names of the properties, which are also the names of the slots of the property-list frames of the faces (see the definition of a property-list frame, page 60), are built as in the following example: if the name of the sensor (camera or light) is S1, the properties will be called visible-S1, occluded-S1, back-S1. The property frames (see page 61) are automatically created or updated.  
merge-shadows specifies whether the cast-shadowed regions corresponding to different occluding faces should be merged or not before back-projection to the faces of the scene (MERGE-LIGHT-PROPERTIES does the same merging operations, but after back-projecting to the scene).
PROJECT-AND-BACK-PROJECT* \( \text{scene sensor} \) \hfill function

PROJECT-AND-BACK-PROJECT* is like PROJECT-AND-BACK-PROJECT, except that it evaluates its arguments.

MERGE-LIGHT-PROPERTIES \( \text{scene light-source} \) \hfill macro

The property regions, obtained in a scene for a light-source using the previous function, are computed by a face-to-face technique, and therefore the occluded areas are split into regions characterized by the face that occludes them (the occluding face considered is the closest one to the sensor).

PROJECT-AND-BACK-PROJECT (see above) and IMAGE (see page 26) allow the user either to merge these split regions for each face before back-projecting them, or to back-project the split regions directly. In the latter case, the user can perform the merging operations later, using MERGE-LIGHT-PROPERTIES. This function makes the union, on every face of the scene, of the split occluded regions for the light-source, in order to get the full consolidated occluded (cast-shadowed) area. The old split regions are saved as a new property under a new name (for a light-source L1, the name is split-occluded-L1), and the new merged property-regions take their previous name (occluded-L1).

An example is showed in page 40

MERGE-LIGHT-PROPERTIES* \( \text{scene light-source} \) \hfill function

MERGE-LIGHT-PROPERTIES* is like MERGE-LIGHT-PROPERTIES, except that it evaluates its arguments.
9. Image and 2-D Properties

9.1. Image
Given a 3-D scene and a sensor (camera), a 2-D image can be generated. The 2-D image consists of 2-D regions, arcs and joints. See paragraph 3.6.5, page 11, for a definition of a 2-D image, and page 62 for a description of a 2-D image frame.

(IMAGE scene camera key (lights NIL) (image-name NIL) (merge-shadows T) )
Generates a 2-D image for the given scene, using the given camera. If no image-name is given for the image, a name is automatically generated (e.g. image-1209). The complete 2-D representation of the image is computed, including regions, arcs, joints, winged-edge relations and back pointers to 3-D elements.
The generation of 3-D properties (back-face, shadow, illuminated) for the specified lights (if not NIL) is also performed (as with the PROJECT-AND-BACK-PROJECT function, page 24).
merge-shadows specifies whether the cast-shadowed regions corresponding to different occluding faces should be merged or not before back-projection to the faces of the scene.

(IMAGE* scene camera key (lights NIL) (image-name 'image) )
IMAGE* is like IMAGE, except that it evaluates its arguments.

An image can be deleted using:

(DELETE-IMAGE image-name )
Deletes the image image-name, with all its joints, arcs, regions.

(DELETE-IMAGE* image-name )
DELETE-IMAGE* is like DELETE-IMAGE, except that it evaluates its argument.
9.2. 2-D Properties

(PAINT-PROPERTY-ON-IMAGE image-name property-name)

Projects the 3-D areas corresponding to the property property-name onto the 2-D regions of the image image-name. The property regions are first transformed using the camera that generated the image, then clipped by the regions of the image. The 2-D properties are stored in the property-list frames of the regions with the slot name image-name (see page 60: the format of a property-list frame is identical in 2-D and 3-D). The property frames (see page 61) are automatically updated.

(PAINT-PROPERTY-ON-IMAGE* image-name property-name)

PAINT-PROPERTY-ON-IMAGE* is like PAINT-PROPERTY-ON-IMAGE, except that it evaluates its arguments.
10. Miscellaneous Functions and Variables

10.1. Functions dealing with Boundary representation

(PREVIOUS-EDGE edge face ) function
Returns the edge that comes before edge on face.

(NEXT-EDGE edge face ) function
Returns the edge that comes after edge on face.

(GET-VERTEX-LIST face ) function
Returns the list of vertices of face. (The vertices are not ordered).

(GET-ORDERED-VERTICES face ) function
Returns the ordered list of vertices of the outer boundary of face.

(GET-ALL-ORDERED-VERTICES face ) function
Returns a list that contains the ordered lists of vertices of the boundaries of face (outer boundary and hole boundaries).

(NEIGHBOR-FACES face ) function
Returns the list of faces that have at least in edge in common with face.

(FACEL-EDGEL-OF-VERTEX vertex ) function
Returns a list that contains the list of edges that have vertex as an end and the list of faces that have vertex as a vertex.

(EDGE-LIST-OF-VERTEX vertex ) function
Returns the list of edges that have vertex as an end.
10.2. Mathematical functions

(DEG) \[\text{function}\]
Sets the \text{*angle-mode*} variable to \text{deg}.

(RAD) \[\text{function}\]
Sets the \text{*angle-mode*} variable to \text{rad}.

\text{*ANGLE-MODE*} \[\text{variable}\]
Determines the unit (\text{deg} or \text{rad}) for the angles.

(SAVE-ANGLE-MODE) \[\text{function}\]
Saves the current \text{*angle-node*}. To be used in conjunction with the \text{restore-angle-mode} function.

(RESTORE-ANGLE-MODE) \[\text{function}\]
Sets the \text{*angle-mode*} to the value it had when calling \text{save-angle-mode}.

(DEG-TO-RAD deg-angle) \[\text{function}\]
Returns the value in radians of an angle in degrees.

(CROSS-PRODUCT vector1 vector2) \[\text{function}\]
Returns the cross-product vector of \text{vector1} and \text{vector2}.

(DOT-PRODUCT vector1 vector2) \[\text{function}\]
Returns the dot-product of \text{vector1} and \text{vector2}.

(LENGTH-OF-VECTOR vector) \[\text{function}\]
Returns the length (norm) of \text{vector}.

(NORM-OF-VECTOR vector) \[\text{function}\]
Divides vector by its norm. Returns the normalized vector.

(ANGLE-BETWEEN-VECTORS vector1 vector2 direction) function
Returns the angle in radians between vector1 and vector2. The vector direction determines the sign of the angle.

(POINT-LINE-DISTANCE xyz line-xyz-1 line-xyz-2) function
Returns the orthogonal distance between a point and a line given by the coordinates of two points.

(HOMO-PROD &rest transf-matrices) function
Returns the matrix obtained by making the matrix-product of the specified transformation matrices.

10.3. Display functions

vantage-window is the default window where all the display actions take place. It has an active region attached to it. When the LEFT mouse button is clicked anywhere inside the vantage-window, the pop-up-menu system is invoked. (Figure 8).

Selection of an item will result in one of the following:

• It will fire a particular function.
  Ex: "Erase-Screen" will clear the vantage-window.

• Further pop-up-menus will show up.
  Ex: "choose-body" will list all the solids defined and the chosen value will become the default for the display system.

• It may ask for some input values.
  Ex: "show-corres-frame" displays the following message. (Figure 9)

Please respond by clicking:
Complete description of the frame = Left-mouse-button
Only the Name = Middle-mouse-button
DISPLAY-CAMERA
Name of the frame that defines the camera used for display of a 3-D object. It is defined like any other camera in Vantage, and can be redefined at will. Its default definition is created by the command:

\[
\text{(camera* 'display-camera '(3000 3000 3000)) which defines an orthogonal projection from the point (3000 3000 3000) pointing to the origin (0 0 0).}
\]

(DRAW-BODY body-name )
Draws the specified body on the vantage-window. The body-name should correspond to the boundary representation.

(DRAW-FACE face-name )
Draws the specified face on the vantage-window.

(DRAW-EDGE edge-name )
Draws the specified edge on the vantage-window.

(DRAW-VERTEX vertex-name radius )
Draws the specified vertex on the vantage-window.

(SHADE-FACE face-name )
Shades the given face depending on the face normal.

(SHADE-POLYGON ink &rest lists )
Shades a region given by the set of lists of vertices. The first one correspond to the outer boundary and the remaining ones are the holes.

(VERTEX-MATCH x-position y-position &optional close )
Returns the nearest displayed vertex on the vantage-window with respect to the given x and y positions. The current position of the mouse is stored in *mouse-x* and *mouse-y*. If more than one vertex is encountered within the range given by close, it will return one of them.
(EDGE-MATCH x-position y-position &optional close)
Returns the nearest displayed edge on the vantage-window with respect to the given x and y positions. If more than one edge is encountered within the range given by close, it will return one of them.

(FACE-MATCH edge1 edge2)
Returns the name of a face that has both edge1 and edge2 as edges.

(FLASH-FACE face-name)
Highlights or erases the existing highlight on the specified face. This is a very useful debugging tool. Multiple calls to flash-face results in a blinking effect.

(FLASH-EDGE edge-name &optional width)
Highlights or erases the existing highlight on the specified edge. This is a very useful debugging tool. Multiple calls to flash-edge results in a blinking effect.

(DRAW-IMAGE image-name)
Draws the specified 2d-image on the vantage-window.

(DRAW-REGION region-name)
Draws the specified 2d-region on the vantage-window.

(DRAW-ARC arc-name)
Draws the specified 2d-arc on the vantage-window.

(DRAW-JOINT joint-name radius)
Draws the specified 2d-joint on the vantage-window.

(SHOW-AXIS &optional length)
Draws the current x, y and z axis on the screen.
*CURRENT-BODY* variable
Name of the last body that has been selected on the choose-body menu.

*CURRENT-IMAGE* variable
Name of the last image that has been selected on the choose-image menu.

(FIT-SCREEN &optional solid-name *current-body* ) macro
Adjusts the display size so that the specified body is entirely inside the window.

(FIT-SCREEN* &optional solid-name *current-body* ) function
FIT-SCREEN* is like FIT-SCREEN, except that it evaluates its argument.

(IMAGE-FIT-SCREEN &optional image-name *current-image* ) macro
Adjusts the display size so that the specified image is entirely inside the window.

(IMAGE-FIT-SCREEN* &optional image-name *current-image* ) function
IMAGE-FIT-SCREEN* is like IMAGE-FIT-SCREEN, except that it evaluates its argument.

(WINDOW-ZOOM ) function
Redisplays the portion of the window selected by two successive middle-mouse-button clicks. The selected region will be enlarged to fit the vantage-window.

*ZOOMF* variable
Controls the scale of the image.

(ZOOM x ) function
Changes the scaling factor of the display (variable *zoomf*). The current value is multiplied by x. The value of x should be greater than 0.

*DASH-LEVEL* variable
Controls the length of the line segments used to draw dashed lines.
(DASH x )  
Changes the *dash-level* variable. The current value is multiplied by x. The value of x should be greater than 0.

*SHADE-LENGTH*  
Controls the vertical distance between two dots used for shading.

(SHADEL x )  
Changes the *shade-length* variable. The current value is multiplied by x. The value of x should be greater than 0.

*SHADE-WIDTH*  
Controls the horizontal distance between two dots used for shading.

(SHADEW x )  
Changes the *shade-width* variable. The current value is multiplied by x. The value of x should be greater than 0.

(DISPLAY-SCENE scene sensor )  
Displays the scene scene as seen from the sensor sensor, with hidden parts hidden. Just paints polygons from back to front.

(DISPLAY-SCENE* scene sensor )  
DISPLAY-SCENE* is like DISPLAY-SCENE, except that it evaluates its arguments.

(DISPLAY-PROPERTY image property-name )  
Displays and shades the property-regions of image for the property property-name.

(DISPLAY-PROPERTY* image property-name )  
DISPLAY-PROPERTY* is like DISPLAY-PROPERTY, except that it evaluates its arguments.
Appendix A
Primitive Solids

(csgnode primitive-1 cub (100 200 150))

(csgnode primitive-2 cyl (50 200 7))
- 1 surface
- 2 curves

(csgnode primitive-3 con (50 150 7))
- 1 surface
- 1 curve
(csgnode primitive-4 tru (100 50 150 7))
- 1 surface
- 2 curves

(csgnode primitive-5 sph (80 5))
- 1 surface

(csgnode primitive-6 iso (100 200 150))
(csgnode primitive-7 rt (100 50 150))

(csgnode primitive-8 2.5p (150
(-20 -50) (50 -30)
(10 25) (30 80) (-25 70)))

(csgnode primitive-9 2.5c (150
(0 -70) (-20 -50) (50 -30)
(10 25) (30 80) (-25 70)))
Appendix B
Examples

This first example shows a lisp file which, when loaded, performs the following operations:

- generation of the CSG tree of an object (body1) from primitives
- creation of a boundary-representation of the object from the CSG tree
- display of the solid on the screen
- definition of a scene containing the object
- definition of a camera
- generation of an image of the scene using the camera
- display of the image on the screen

;; Save current angle unit (degrees or radians)
(save-angle-mode)
;;
;; Set angle unit to degrees
(setq 'angle-mode 'deg)
;;
;; Define csg representation for body1
(csgnode "b1" 'cu '(500 300 111.5) :trans '(0 -68.1 49.25 0 0 0))
(csgnode "b2" 'cyl '(120 50 10) :trans '(-130 6.9 6.5 0 0 -90))
(csgnode "b3" 'mov 'b2 :trans '((260 0 0 0 0 0)))
(csgnode "b4" 'cu '(3000 3000 100) :trans '(0 0 155 0 0 0))
(csgnode "b5" 'uni 'b1 b2))
(csgnode "b6" 'uni 'b5 b3))
(csgnode "body1" 'dif 'b6 b4) :fast 'all)
;;
;; Set the angle unit to its previous value
(restore-angle-mode)
;;
;; Generate boundary representation for body1 (called body1z)
(boun-rep 'body1)
;;
;; Compute scaling and translation factors so that body1 fits on
;; the display window, and draw body1. The camera is the current
;; "display-camera", which has a default definition, but which can be
;; redefined
(fit-screen 'body1)
;;
;; Define 3d scene
(scene 'my-scene '(body1))
;;
;; Define a camera
(camera 'caml '(2000 1000 500) :focal 5)
;;
;; Generate 2D description
(image 'my-scene 'caml :image-name 'my-image)
;;
;; Compute scaling and translation factors so that my-image fits on
;; the display window, and draw my-image
(image-fit-screen 'my-image)
;;
This second example shows an interactive session in which operations similar to the ones of the previous example are performed, plus the following operations:

- definition of a light-source
- generation of the 3D properties of the scene for the light-source
- generation of the 2D properties of the image by projection of the 3D properties of the scene
- display of the 2D property regions

Figures B-1 and B-2 show the resulting image and the property-regions associated with the light-source.
> (csgnode a1 cu (100 100 100))
A1
> (csgnode a2 cu (80 80 200))
A2
> (csgnode a3 cu (80 200 80))
A3
> (csgnode a4 cu (200 80 80))
A4
> (csgnode a5 dif (a1 a2))
A5
> (csgnode a6 dif (a5 a3))
A6
> (csgnode a7 dif (a6 a4) :fast all)
A7
> (csgnode ground cu (1000 1000 10) :trans (0 0 -100 0 0 0))
GROUND
> (boun-rep a7)
A7
> (boun-rep ground)
GROUND
> (scene s1 (a7 ground))
S1
> (camera cl (300 -200 450) :focal 1)
C1
> (light-source l1 (-200 300 450) :focal 1)
L1
> (image s1 cl :lights (l1) :image-name il :merge-shadows nil)
I1
> (image-fit-screen il)
I1
> (paint-property-on-image il back-11)
BACK-L1
> (paint-property-on-image il occluded-11)
OCCLUDED-L1
> (paint-property-on-image il visible-11)
VISIBLE-L1
> (merge-light-properties s1 l1)
L1
> (paint-property-on-image il occluded-11)
OCCLUDED-L1
> (display-property il back-11)
BACK-L1
> (display-property il split-occluded-11)
SPLIT-OCCLUDED-L1
> (display-property il occluded-11)
OCCLUDED-L1
> (display-property il visible-11)
VISIBLE-L1
Figure B-1: Image i1, plain and with shadows (after window-zooming)

Figure B-2: I1 property-regions projected on i1
Appendix C
Standard Frames

The next pages give the definition of the frames used in VANTAGE. For each type of frame, the corresponding slots are listed, along with a brief description of each. Optional slots are marked with a "*".
Description: Representation of a CSG-node.

Frame:

(CSG-NODE-NAME
 (is-a)
 (class)
 (type)
 (parameters)
 (rigid-motion)
 (node-used-by-list)
 (boundary-rep)
 (group-approximate)
 (merge)
 * (node-left)
 * (node-right)
 * (fast)
 * (surface-list)
 * (curve-list))

Slots:

is-a
 Value: csg-node.

class
 Value: either primitive, or operation.
 Specifies whether the node is a leaf-node (primitive solid) or results from an operation performed on its child node(s).

type
 Value: either a primitive type (e.g. cube, cylinder, cyl, etc.) or an operation name (e.g. union, dif, move, mir, etc.).
 This slot specifies the type of primitive or the type of operation the node corresponds to.

parameters
 Value: List of float numbers.
 For a primitive solid, the parameters that define it.

rigid-motion
 Value: motion-matrix.
 Defines the coordinate system attached to the node.

node-used-by-list
 Value: list of csg-nodes.
 The list contains the csg-nodes that are defined using the current node, i.e. the parent nodes of the node in the csg-tree.

boundary-rep
 Value: 3d-body.
 inverse: body-csg-node.
 Points to the boundary-representation of the body defined by the node.
group-approximate
Value: T.
Is T when the grouping of the approximated faces and edges has been done.

merge
Value: T.
Is T when some faces have been merged.

node-left
Value: CSG-NODE.
For a solid that results from an operation, the left child of the node.

node-right
Value: CSG-NODE.
For a solid that results from an operation, the right child of the node.

fast
Value: T.
When it is T, then the boundary representation of the child nodes of the node will not be copied/saved before performing on them the operation that will create the boundary representation of the node.

surface-list
Value: list of surfaces.
List of the non-planar surfaces contained in the body.

curve-list
Value: list of curves.
List of the non-linear curves contained in the body.
Description: Representation of a solid or body.

Frame:

(3D-BODY-NAME
(is-a)
  (body-csg-node)
  (body-rigid-motion)
  (body-face-list)
  (body-vertex-list)
  (body-cfg-list)
* (body-app-grouped-faces)
* (body-app-grouped-edges)
* (body-merged-faces))

Slots:

  is-a
    Value: 3d-body.

  body-csg-node
    Value: csg-node.
    Inverse: boundary-rep
    Points to the csg-node that defines the body.

  body-rigid-motion
    Value: motion-matrix.
    The transformation gives the location of the current body-coordinates frame in
    the world-coordinates.

  body-face-list
    Value: list of 3d-faces.
    Inverse: face-body.
    Lists all the faces of the body.

  body-edge-list
    Value: list of 3d-edges.
    Inverse: edge-body.
    Lists all the edges of the body.

  body-vertex-list
    Value: list of 3d-vertices.
    Inverse: vertex-body.
    Lists all the vertices of the body.

  body-cfg-list
    Value: list of lists of 3d-faces.
    Lists all the closed groups of connected faces (cfg) of the body.

  body-app-grouped-faces
    Value: list of 3d-faces.
    Lists all the faces of the body that have been obtained by grouping a set of
connected faces that approximate a same surface.

body-app-grouped-edges
Value: list of 3d-edges.
Lists all the edges of the body that have been obtained by grouping a set of connected edges that approximate a same curve.

body-merged-faces
Value: list of 3d-faces.
Lists all the faces of the body that have been obtained by merging connected faces.
Description: Representation of a face of a body.

Frame:

(3D-FACE-NAME
   (is-a)
   (face-body)
   (face-type)
   (face-geometry)
   (out-boun-list)
   (hole-boun-list)
   * (face-surface)
   * (face-class)
   * (face-parent)
   * (face-subdivision)
   * (face-children)
   * (face-properties)
   * (app-grouped-out-boun-list)
   * (app-grouped-hole-boun-list))

Slots:

is-a
   Value: 3d-face.

face-body
   Value: 3d-body.
   Inverse: body-face-list.
   Points to the 3d-body that contains the face.

face-type
   Value: either plane, cyl, sph, con
   Gives the type of the surface that contains the face.

face-geometry
   Value: list of parameters.
   For a planar face, lists the coordinates of the normal vector of the face and the orthogonal distance between the face and the origin.

out-boun-list
   Value: list of lists of 3d-edges.
   Lists the outer boundaries of the face. For a planar face, there is only one outer-boundary.

hole-boun-list
   Value: list of lists of 3d-edges.
   Lists the boundaries of the holes of the face.

face-surface
   Value: surface.
   Points to the surface that contains the face.
face-class
Value: either global, app, or merge.
Indicates whether and how this face was combined with other faces to generate a parent face. A global face has no parent face. An app face has a parent face obtained by grouping a set of connected faces that approximate a same surface. A merge face has a parent face obtained by merging a set of connected faces.

face-parent
Value: 3d-face.
Inverse: face-children.
Points to the parent face of this face.

face-subdivision
Value: either merge or app.
Indicates whether and how this face is divided into children faces. It is app if the face was obtained by grouping a set of connected faces that approximate a same surface. It is merge if the face was obtained by merging a set of connected faces.

face-children
Value: list of 3d-faces.
Inverse: face-parent.
Points to the list of faces that generated this face.

face-properties
Value: property-list.
Points to the frame that lists the properties of the face.

app-grouped-out-boun-list
Value: list of lists of 3d-edges.
Lists the outer boundaries of the face, replacing every set of connected approximated edges by their parent edge.

app-grouped-hole-boun-list
Value: list of lists of 3d-edges.
Lists the boundaries of the holes of the face, replacing every set of connected approximated edges by their parent edge.
Description: Representation of an edge of a body.

Frame:

\[
\text{(3D-EDGE-NAME)} \\
(\text{is-a}) \\
(\text{edge-body}) \\
(\text{edge-type}) \\
(\text{p-face}) \\
(\text{n-face}) \\
(\text{pcw}) \\
(\text{nccw}) \\
(\text{pcw}) \\
(\text{ncw}) \\
(\text{p-vertex}) \\
(\text{n-vertex}) \\
* (\text{edge-curve}) \\
* (\text{edge-kind}) \\
* (\text{edge-class}) \\
* (\text{edge-parent}) \\
* (\text{edge-subdivision}) \\
* (\text{edge-children}) \\
* (\text{app-grouped-p-face}) \\
* (\text{app-grouped-pcw}) \\
* (\text{app-grouped-pccw}) \\
* (\text{app-grouped-nccw}) \\
* (\text{app-grouped-ncw})
\]

Slots:

\text{is-a}  \\
Value: 3d-edge.

\text{edge-body}  \\
Value: 3d-body. \\
Inverse: body-edge-list. \\
Points to the 3d body that contains the edge.

\text{edge-type}  \\
Value: either line, cir, or any combination of 2 surfaces chosen among plane, 
\text{cyl, con, sph (e.g. plane-cyl, con-con, cyl-sph, etc).} \\
Gives the type of the curve that contains the edge, or the types of the 2 surfaces 
whose intersection contains the edge.

\text{p-face}  \\
Value: 3d-face. \\
Points to the p-face in the winged-edge representation of this edge.

\text{n-face}  \\
Value: 3d-face. \\
Points to the n-face in the winged-edge representation of this edge.
pcw
Value: 3d-edge.
Points to the pcw-edge in the winged-edge representation of this edge.

ncw
Value: 3d-edge.
Points to the nccw-edge in the winged-edge representation of this edge.

pccw
Value: 3d-edge.
Points to the pccw-edge in the winged-edge representation of this edge.

ncw
Value: 3d-edge.
Points to the nccw-edge in the winged-edge representation of this edge.

p-vertex
Value: 3d-vertex.
Points to the p-vertex in the winged-edge representation of this edge.

n-vertex
Value: 3d-vertex.
Points to the n-vertex in the winged-edge representation of this edge.

data
Value: 3d-edge.
Points to the edge-curve.

edge-kind
Value: aux.
aux indicates that the edge is an auxiliary edge which divides a curved surface into auxiliary planar surfaces for the purpose of approximation.

edge-class
Value: either global or app.
Indicates whether this face was combined with other faces to generate a parent face. A global edge has no parent edge. An app face has a parent face obtained by grouping a set of connected faces that approximate a same curve.

data
Value: 3d-edge.
Points to the edge-parent of this edge.

edge-parent
Value: 3d-edge.
Points to the parent edge of this edge.

edge-subdivision
Value: app.
This slot indicates whether this edge is divided into children edges. It is app if the edge was obtained by grouping a set of connected edges that approximate a same curve.

edge-children
Value: list of 3d-edges.
Points to the list of edges that generated this edge.

app-grouped-p-face
Value: 3d-face.
Parent-face of the p-face of the edge.

app-grouped-n-face
Value: 3d-face.
Parent-face of the n-face of the edge.
app-grouped-pcw
Value: 3d-edge.
Parent-edge of the pcw-edge of the edge.

app-grouped-nccw
Value: 3d-edge.
Parent-edge of the nccw-edge of the edge.

app-grouped-pccw
Value: 3d-edge.
Parent-edge of the pccw-edge of the edge.

app-grouped-ncw
Value: 3d-edge.
Parent-edge of the ncw-edge of the edge.

Figure C-1: Winged-edge representation
Description: Representation of a vertex of a body.

Frame:

(3D-VERTEX-NAME
 (is-a)
 (vertex-body)
 (one-of-the-edges)
 (xyz-values)
 * (display-xy))

Slots:

is-a  Value: 3d-vertex.

vertex-body  Value: 3d-body.
  Inverse: body-vertex-list.
  Points to the 3d body that contains the vertex.

one-of-the-edges  Value: 3d-edge.
  Points to one of the 3d edges that have this point as an end point.

xyz-values  Value: list of three numbers.
  Gives the list (x-coordinate, y-coordinate, z-coordinate) of the vertex with respect to the body coordinates.

display-xy  Value: list of two integers.
  Gives the coordinates of the vertex with respect to the screen coordinates.
Description: Representation of a motion matrix.

Frame:

(MOTION-MATRIX-NAME
  (is-a)
  (matrix-name)
  (first-row)
  (second-row)
  (third-row))

Slots:

  is-a
    Value: motion-matrix.

  matrix-name
    Value: array (3 4) of float numbers.
    Points to the matrix, defined by the make-array function.

  first-row
    Value: list of 4 float numbers.
    Lists the elements of the first row of the matrix.

  second-row
    Value: list of 4 float numbers.
    Lists the elements of the second row of the matrix.

  third-row
    Value: list of 4 float numbers.
    Lists the elements of the third row of the matrix.
Description: Definition of a surface.

Frame:

(SURFACE-NAME
  (is-a)
  (type)
  (parameters)
  (rigid-motion))

or:

(SURFACE-NAME
  (is-a)
  (type)
  (move)
  (rigid-motion))

or:

(SURFACE-NAME
  (is-a)
  (type)
  (mirror)
  (mirror-plane)
  (rigid-motion))

Slots:

  is-a
    Value: surface.

  type
    Value: either cyl, con, or sph.
    Geometric type of the surface.

  parameters
    Value: list of float numbers defining the surface.
    The list contains the radius for a cylinder and a sphere, and a radius and a height for a cone.

  rigid-motion
    Value: motion-matrix.
    The motion-matrix gives either the position of the surface in the world coordinates frame, or, when the move or mirror slot exists, the transformation to apply to the specified surface.

  move
    Value: surface.
    If specified, indicates that the surface is obtained by applying the specified rigid-motion to the specified surface.
mirror
Value: surface.
If specified, indicates that the surface is obtained by applying the specified mirror operation to the specified surface, and then by applying the specified rigid-motion.

mirror-plane
Value: list of 4 float numbers.
Defines the mirror plane by listing the coordinates of its normal vector and the orthogonal distance between the plane and the origin.
Description: Definition of a curve

Frame:

(CURVE-NAME
  (is-a)
  (type)
  (parameters)
  (rigid-motion)
  (inter))

or:

(CURVE-NAME
  (is-a)
  (type)
  (move)
  (rigid-motion))

or:

(CURVE-NAME
  (is-a)
  (type)
  (mirror)
  (mirror-plane)
  (rigid-motion))

Slots:

  is-a  Value: curve.

  type  Value: either cir or any combination of 2 surfaces chosen among plane, cyl, con, sph (e.g. plane-cyl, con-con, cyl-sph, etc). Gives the type of the curve, or the types of the 2 surfaces whose intersection generate the curve.

  parameters  Value: list of float numbers defining the curve.

  rigid-motion  Value: motion-matrix.

    The motion-matrix gives either the position of the curve in the world coordinates frame, or, when the move or mirror slot exists, the transformation to apply to the specified curve.

  move  Value: curve.
If specified, indicates that the curve is obtained by applying the specified rigid-motion to the specified curve.

**mirror**
- **Value:** curve.
- If specified, indicates that the curve is obtained by applying the specified mirror operation to the specified curve, and then by applying the specified rigid-motion.

**mirror-plane**
- **Value:** list of 4 float numbers.
- Defines the mirror plane by listing the coordinates of its normal vector and the orthogonal distance between the plane and the origin.

**inter**
- **Value:** list containing 2 surfaces or one surface and one plane.
- Points to the 2 surfaces whose intersection defines the curve. If one surface is a plane, it is specified by a list containing the coordinates of its normal vector and the orthogonal distance between the plane and the origin.
Description: Definition of a 3d scene.

Frame:

(3D-SCENE-NAME
  (is-a)
  (csg-node-list)
  (light-list)
  (x-max)
  (y-max)
  (z-max)
  (x-min)
  (y-min)
  (z-min))

Slots:

  is-a   Value: 3d-scene.

  csg-node-list
    Value: list of csg-nodes.
    Lists the bodies that are in the scene.

  light-list
    Value: list of sensors.
    Lists the light-sources that have been used in the scene.

  x-max, y-max, z-max, x-min, y-min, z-min
    Value: float numbers.
    Maximum and minimum x, y, z coordinates of the scene.
Description: Definition of a sensor.

Frame:
(SENSOR-N AME
  (is-a)
  (type)
  (parameters)
  (rigid-motion)
  * (focal-length)
  * (limit-angle))

Slots:

  is-a  Value: sensor.

  type  Value: either camera or light.

  rigid-motion  Value: rigid-motion Defines the frame of coordinates of the sensor. The z-axis of this frame is the "viewing" direction, pointing from the object to the sensor.

  parameters  Value: list of 6 float numbers.
             Lists the parameters (x y z roll pitch yaw) that define the frame of coordinates of the sensor.

  focal  Value: float number.
             Focal-length of the sensor. Gives the distance between the projection-plane and the sensor. For a light-source, no specified focal-length means a parallel light-source, whereas a specified focal-length corresponds to a perspective light-source.

  limit-angle  Value: float number, or NIL.
             Maximum angle (in degrees) between the normal of a face and the projection direction, for which the face is visible. NIL corresponds to a limit-angle of 90 degrees.
Description: Representation of properties for a particular 3D face or 2D region.

Frame:

(PROPERTY-LIST-NAME
  (is-a)
  (property-1)
  (property-2)
  .
  ...
)

Slots:

  is-a  Value: property-list.

  property-1, property-2, etc.

  Each slot represents a different property specified by the name of the slot.
  Value: list of polygons, where a polygon is a list of boundaries (outer, then
  hole(s)), and where a boundary is a list of vertices (each one represented by a
  list containing its x and y coordinates (in 2-D), or x, y and z coordinates (3-D)),
  or T.

  Defines the region(s) of the face where the property applies. If T, the property
  applies to the whole face.
Description: Each property frame has a name that is the name of a property (e.g. occluded-L1), and lists the 3-D faces and the 2-D regions that have that property.

Frame:

(PROPERTY-NAME
 (is-a)
 (3d-faces)
 (2d-regions))

Slots:

 is-a  Value: property.

3d-faces  Value: list of faces (in one or several scene(s)) that have the property.

2d-regions  Value: list of regions (in one or several image(s)) that have the property.
Description: Definition of a 2d-image.

Frame:

<table>
<thead>
<tr>
<th>2D-IMAGE-NAME</th>
</tr>
</thead>
<tbody>
<tr>
<td>(is-a)</td>
</tr>
<tr>
<td>(image-3d-scene)</td>
</tr>
<tr>
<td>(image-camera)</td>
</tr>
<tr>
<td>(image-light-source-list)</td>
</tr>
<tr>
<td>(image-region-list)</td>
</tr>
<tr>
<td>(image-arc-list)</td>
</tr>
<tr>
<td>(image-joint-list)</td>
</tr>
<tr>
<td>(image-bounding-box)</td>
</tr>
</tbody>
</table>

Slots:

- **is-a**: Value: 2d-image.
- **image-3d-scene**: Value: 3d-scene.
  Specifies the 3d scene that is projected on the image.
- **image-camera**: Value: sensor.
  Specifies the camera that is used to generate the image.
- **image-region-list**: Value: list of 2d-regions.
  Inverse: region-image.
  Lists all the regions of the image that result from the projection of a 3d-face.
- **image-arc-list**: Value: list of 2d-arcs.
  Inverse: arc-image.
  Lists all the arcs (line-segments) of the image.
- **image-joint-list**: Value: list of 2d-joints.
  Inverse: joint-image.
  Lists all the joints (vertices) of the image.
- **image-bounding-box**: Value: list of 4 float numbers.
  Lists the minimum and maximum coordinates of the image (x-min y-min x-max y-max).
Description: Representation of a region of a 2d-image

Frame:

2D-REGION-NAME
(is-a)
(region-image)
(3d-face)
(region-bounding-box)
(region-out-boun-list)
(region-hole-boun-list)
* (region-properties))

Slots:

is-a
  Value: 2d-region.

region-image
  Value: 2d-image.
  Inverse: image-region-list.
  Points to the 2d-image that contains the region.

3d-face
  Value: 3d-face.
  Points to the 3d-face that generated the region.

region-bounding-box
  Value: list of 4 float numbers.
  Lists the minimum and maximum coordinates of the region on the image (x-min y-min x-max y-max).

region-out-boun-list
  Value: list of 2d-arcs.
  Lists the outer boundary of the region.

region-hole-boun-list
  Value: list of lists of 2d-arcs.
  Lists the boundaries of the holes of the region.

region-properties
  Value: property-list.
  Points to the frame that lists the properties of the region.
Description: Representation of an arc of a 2d-image.

Frame:

(2D-ARC-NAME
(is-a)
(arc-image)
(3d-edge)
(p-joint)
(n-joint)
(p-region)
(n-region)
(pcw)
(nccw)
(nrcw))

Slots:

is-a Value: 2d-arc.
arc-image Value: 2d-image.
Inverse: image-arc-list.
Points to the 2d image that contains the arc.
3d-edge Value: 3d-edge.
Points to the 3d-edge that generated the arc.
p-joint Value: 2d-joint.
Points to the p-joint in the winged-edge representation of this arc.
n-joint Value: 2d-joint.
Points to the n-joint in the winged-edge representation of this arc.
p-region Value: 2d-region.
Points to the p-region in the winged-edge representation of this arc.
n-region Value: 2d-region.
Points to the n-region in the winged-edge representation of this arc.
pcw Value: 2d-arc.
Points to the pcw-arc in the winged-edge representation of this arc.
nccw Value: 2d-arc.
Points to the nccw-arc in the winged-edge representation of this arc.
pc cw  
Value: 2d-arc.
Points to the pccw-arc in the winged-edge representation of this arc.

ncw  
Value: 2d-arc.
Points to the ncw-arc in the winged-edge representation of this arc.
Description: Representation of a joint of an image.

Frame:

(2D-JOINT-NAME
(is-a)
(joint-image)
(x)
(y)
* (3d-vertex-list)
* (display-xy))

Slots:

is-a Value: 2d-joint.

joint-image Value: 2d-image.
Inverse: image-joint-list.
Specifies the 2d-image that contains the joint.

x Value: float number.
Gives the x-coordinate of the joint with respect to the camera coordinates.

y Value: float number.
Gives the y-coordinate of the joint with respect to the camera coordinates.

3d-vertex-list Value: list of 3d-vertices.
Specifies the 3d-vertex or 3d-vertices that generated the joint.

display-xy Value: list of two integers.
Gives the coordinates of the joint with respect to the screen coordinates.
Appendix D  
Framekit+ functions

FRAMEKIT is a frame-based knowledge representation, written in COMMON LISP, that provides the basic mechanisms of frames, inheritance, demons and views. It has been developed by Center for Machine Translation, Carnegie Mellon University. This section explains briefly some of the important and heavily used FRAMEKIT functions. This is by no means a complete description.

[Warning::Some of the key word arguments to the functions and the like are omitted here.] The users are advised to go through the separate document titled "The FRAMEKIT User’s Guide".

D.1. Frames

A frame is a multi-level data structure, much like a record structure in traditional programming languages, that is used to store information used by COMMON LISP programs. A large collection of frames is sometimes called a knowledge base. Because frames also support demons and inheritance they are particularly useful for representing the knowledge in AI programs.

Frames are abstract data types comprised of slots, facets, views and fillers. Each frame can have any number of slots. Each slot can have any number of facets, and each facet can have any number of views and each view can have any number of fillers. Frames differ from traditional record structures in that slots, facets and views can be allocated and removed at run time. There are some facets that are pre-defined by FRAMEKIT to handle demons and inheritance.

The general structure of a frame is as follows.

```lisp
(FrameName
 (SlotName (VALUE (VIEW list-of-values))
 (VIEW list-of-values))
 (IF-ADDED demon-list)
 (IF-NEEDED demon-list)
 (IF-ERASED demon-list)
 (RESTRICTIONS predicate-list)
 (DEFAULT list-of-values)
 ...
 (user-defined .........)
 ({... ..........})
 (SlotName ....)
)```


Please refer to FRAMEKIT manual for the complete syntax.

D.2. Frame creation

**(CREATE-FRAME frame)** *function*

The argument to CREATE-FRAME must be a symbol. The symbol is checked to see if a frame of that name already exists; if not, a new frame is created and added to *FRAME-LIST*. The frame name is returned if the creation took place, otherwise NIL is returned.

**(CREATE-SLOT frame slot)** *function*

If the frame already exists, CREATE-SLOT checks to see if the slot is already present; if not, a new slot is created. If the frame doesn't exist, it will either automatically create the frame or print a warning message. The slot name is returned if a new slot is created; otherwise NIL is returned.

**(CREATE-FACET frame slot facet)** *function*

If the frame and slot already exist, CREATE-FACET checks to see if the facet is already present; if not, a new facet is created. If either the frame or the slot doesn't exist, it will either automatically create them or print a warning message. The facet name is returned if a new facet is created; otherwise NIL is returned.

Examples:

```
> (create-frame 'dog)
> (create-slot 'dog 'weight)
> (create-facet 'tiger 'weight 'value)
> (create-facet 'cat 'race 'if-needed)
```

**(MAKE-FRAME frame-name &rest full-frame)** *macro*

MAKE-FRAME is a macro for defining frames in a file or at the Lisp top-level. The first argument is interpreted as the name of the frame to create; the rest of the arguments are interpreted as fully-specified slot definitions. The frame name is returned. For example:

```
> (make-frame my-frame
   (slot1 (facet1 (view1 filler-list1)
              (view2 filler-list2)))
```
Any number of slots may be defined, each with any number of facets. Each facet may contain any number of views, each with any number of fillers.

**MAKE-FRAME**

MAKE-FRAME* is like MAKE-FRAME, except that it evaluates its arguments, and the slot definitions must be specified as a single list.

**MK-FRAME**

MK-FRAME is another macro for defining frames in a file or at the Lisp top-level; unlike MAKE-FRAME, MK-FRAME accepts slot definitions in abbreviated form:

```lisp
(mk-frame frame-name &rest fullframe)
```

Each filler is placed in the COMMON view of the VALUE facet of the specified slot.

**MK-FRAME**

MK-FRAME* is like MK-FRAME, except that it evaluates its arguments, and the slot definitions must be specified as a single list.

### D.3. Update Functions

**ADD-VALUE**

Adds a filler to the VALUE facet in the specified slot, unless that filler already exists.

**ADD-VALUES**

ADD-VALUES is just like ADD-VALUE, except that it accepts a list of fillers to add to the
VALUE facet all at once.

(ADD-FILLER frame slot facet filler)
Similar to ADD-VALUE but operates on the specified facet instead of the VALUE facet.

(ADD-FILLERS frame slot facet filler-list)
Similar to ADD-VALUES but operates on the specified facet instead of the VALUE facet.

(ERASE-VALUES frame slot)
Erases all the fillers of the VALUE facet of the specified slot.

(ERASE-FILLER frame slot facet filler)
Removes the given filler from the specified facet of the slot.

(ERASE-FACET frame slot facet)
Deletes the named FACET from the named SLOT of the frame.

(ERASE-SLOT frame slot)
The given SLOT is removed from the frame. If the slot is a relation, the inverse link will be erased in the corresponding frame.

(ERASE-FRAME frame)
The frame is erased, by erasing slots one by one (thus eliminating any inverse links and then erasing the frame itself). Returns nil.

(ERASE-FRAMES frame-list)
ERASE-FRAME is applied on each element of the frame-list.

(REPLACE-VALUE frame slot filler)
A composition of ERASE-VALUES and ADD-VALUE. Erases the VALUE facet fillers for the specified view, and adds the given filler to the VALUE facet.
(REPLACE-FILLER frame slot facet filler )
A composition of ERASE-FILLER and ADD-FILLER. Erases the facet fillers and adds the given filler to that facet.

Examples:

> (add-filler 'edge123 'pcw 'value 'edge86)
> (add-value 'dog 'color 'white)
> (replace-value 'dog 'color 'brown)
> (erase-values 'dog 'color)
> (erase-facet 'dog 'race 'if-needed)
> (erase-slot 'edge123 'pcw)
> (erase-frame 'dog)

D.4. Access Functions

(GET-VALUES frame slot )
Returns a list of fillers of the VALUE facet in the specified slot.

(GET-FILLERS frame-name slot facet )
Returns a list of fillers of the specified facet.

(SLOT-NAMES frame )
Returns a list containing the names of the slots in the specified frame.

(FACET-NAMES frame slot )
Returns a list containing the names of the facets in the specified slot.

D.5. Miscellaneous Functions and Variables

(FRAME-P frame )
Returns the frame name if it exists otherwise nil.

*FRAME-LIST*
variable
When FRAMEKIT creates a frame, its name is added to *FRAME-LIST*. When a frame is erased, it is removed from *FRAME-LIST*. The order of the frames in *FRAME-LIST* indicates from left to right the order in which they were created.

*FKTRACE*  
If *FKTRACE* is non-NIL, FRAMEKIT will print trace information concerning each FRAMEKIT action that is evaluated. Although this results in a lot of output, it is useful for debugging purposes, since operations that are not always evident to the user (like demon invocation and automatic structure creation) become visible when tracing is enabled. Initial value is NIL.

*FKWARN*  
If *FKWARN* is non-NIL, FRAMEKIT will inform the user about warning conditions that are non-fatal, but require some user notification (e.g., trying to add a filler to a facet when that filler is already present). Initial value is nil.

!FRAME, !SLOT, !FACET and !FILLER are the special variables which store the current frame, slot, facet and filler respectively at the time a demon mechanism is invoked. They can be used by the functions fired at that moment.
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