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Conservative Volumetric Visibility with Occluder Fusion

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Abstract

Visibility determination is a key requirement in a wide range of graphics algorithms. This paper introduces a new approach to the computation of volume visibility, the detection of occluded portions of space as seen from a given region. The method is conservative and classifies regions as occluded only when they are guaranteed to be invisible. It operates on a discrete representation of space and uses the opaque interior of objects as occluders. This choice of occluders facilitates their extension into adjacent opaque regions of space, in essence maximizing their size and impact. Our method efficiently detects and represents the regions of space hidden by such occluders. It is the first one to use the property that occluders can also be extended into empty space provided this space is itself occluded from the viewing volume. This proves extremely efficient for computing the occlusion by a set of occluders, effectively realizing occluder fusion. An auxiliary data structure represents occlusion in the scene and can then be queried to answer volume visibility questions. We demonstrate the applicability to visibility preprocessing for real-time walkthroughs and to shadow-ray acceleration in both cases.

1 Introduction

Determining visibility is central in many computer graphics algorithms. If visibility information were available in advance, scanline renderers would not need to rasterize hidden geometry, and ray-tracers could avoid tracing shadow rays from points in shadow and testing objects that could not be hit. However, computing and storing all possible view configurations for a scene — the aspect graph — is impractical for complex scenes. Even calculating all the visual events in a scene has very high complexity [9] and poses numerical stability problems.

It is generally easier to conservatively overestimate the set of potentially visible objects (PVS [1, 26]) for a certain region of space (referred to as a “viewcell” throughout this paper). While effective methods exist to detect occlusions in indoor scenes [1, 26] and terrain models [24], in more general types of complex scenes previous approaches [4, 6, 21] consider single convex occluders only to determine objects, or portions of space, that are completely hidden from the viewcell. This is known as volume visibility.

In many cases, objects are hidden due to the combination of many, not necessarily convex, occluders. This situation is exacerbated by the lack of large polygons in today’s finely tessellated models. Figure 7 in Section 4.3 compares the number of occlusions detected using single convex occluders to the number detected with our method. Combining the effect of multiple, arbitrary occluders is complicated by the many different kinds of visual events that occur between a set of objects [9] and by various geometric degeneracies.

As a new solution to these problems, this paper proposes to calculate volume visibility on a conservative discretization of space. Occlusion is explicitly represented in this discretization and can be queried to retrieve visibility information for arbitrary scene objects — either static, dynamic or newly added.

We use opaque regions of space as blockers and automatically derive them from the scene description instead of expecting large convex occluders to be present in the scene. Our representation decouples the scene complexity from the accuracy and computational complexity at which visibility is resolved.

We show that hidden regions of space are valid blockers and that any opaque blocker can be extended into such regions of space. This effectively combines — fuses [32] — one blocker with all the other blockers that have caused this region to be occluded and results in a dramatic improvement in the occlusions detected. Collections of occluders need not be connected or convex.

The rest of the paper is organized as follows. In the next section, we review previous approaches to visibility computation with special emphasis on volume visibility methods. Next, we describe our approach in 2D and then extend it to 3D and 2 1/2 D. We present results for PVS computation and reducing the number of shadow rays in ray-tracing. We conclude with a discussion of our results and suggestions for future work.

2 Previous Work

The central role of visibility has resulted in many previously published approaches. We classify them into the following three categories: exact, point-sampled and conservative visibility computations and focus the discussion on volume visibility approaches. Examples of exact visibility representations are the aspect graph [20] or the visibility skeleton [9] and exact shadow boundaries [3, 8, 23, 27]. As mentioned above, they are impractical for complex scenes.

Point-sampling algorithms calculate visibility up to the accuracy of the display resolution [5, 7, 13]. One sample ray is sent into the scene and the obtained visible surface is reused over an area (e.g. a pixel or solid angle on the hemisphere). Today’s most widely used approach is a hardware-accelerated z-buffer [2] or its variants, the hierarchical z-buffer [14] and hierarchical occlusion maps [32]. Visibility results obtained from these algorithms cannot be extended to volume visibility without introducing error. For volume visibility, projections are not feasible, as no single center of projection is appropriate.

To cope with the complexity of today’s models, researchers have investigated conservative subsets of the hidden scene portion. Airey
et al. [1] and Teller et al. [26, 28] propose visibility preprocessing for indoor scenes. They identify objects that are visible through sequences of portals. Yagel et al. [31] apply similar ideas in 2D for visibility in caves. Stewart [24] provides a solution for the case of terrain. Unfortunately, these algorithms do not generalize to volume visibility for more general types of complex scenes.

Conservative, but accurate, volume visibility computations for general scenes are limited to considering one convex occluder at a time for identifying hidden objects. Cohen-Or et al. [6] find hidden buildings in cities. Saona-Vazquez et al. [21] apply a similar strategy to the nodes in an octree. They intersect the PVS as seen from the eight corners of each voxel to obtain the PVS for the voxel. Coorg et al. [4] use supporting planes between the blocker and an occludee to determine occlusion. These planes also allow them to determine when the occluder will no longer hide the occludee. All these single occluder approaches share the difficulties of identifying good occluders, and none performs occluder fusion. Unfortunately, in practice many scenes do not contain any large polygons or convex objects. Durand [11] calculates volume visibility by projecting potential occluders onto planes. He modifies point-sampled projections and convolution to obtain a conservative algorithm.

In volume visibility it seems to be inherently difficult to combine the effects of multiple occluders in a provably accurate and efficient way. We believe that this is due to the nature of the occluders considered — convex polygons or objects — and because the portions of occluded space have not been explicitly represented or used in the computations.

Our visibility algorithm works entirely on a volumetric scene representation. We propose to abandon considering polygons as occluders, and instead let the volumetric nature of opaque objects occlude the space behind them. Several authors [4, 6, 10, 21] have required convex decompositions of arbitrary objects in order for their algorithms, operating on convex blockers, to work. Indeed, volumetric representations, such as octrees, provide such a convex decomposition. They also represent space itself so that efficient blockers can be found using occluded regions as described below. In our approach, we construct shafts around blockers as seen from the viewpoint similar to Haines et al.’s shaft culling [16] and Teller et al.’s inter-cell visibility algorithm [28]. The difference is that Haines’ shafts lie between the viewpoint and the occludee, whereas ours lie behind the occluder as seen from the viewpoint.

### 3 Definitions and Overview

Our goal is to determine occlusion from within a viewcell on a conservative discretization of space employing these definitions:

- A **viewcell** is an axis-aligned box that is either identical to or known to bound a volume of viewpoints of interest.
- An **occluder** (or blocker) is an axially-aligned box causing occlusion by opacity or other properties established by the algorithm (see Sections 4.2 and 4.3).
- A **shaft** is the convex intersection of half-spaces constructed from the visual events between the viewcell and the occluder. If the viewcell is considered as an extended light source, the volume inside the shaft is identical to the umbra of the occluder.
- A leaf voxel in the spatial subdivision is labeled **opaque** if it is completely inside an object, **empty** if it is completely outside all objects, or **boundary** [22] if it contains a portion of any object’s surface. For this classification we require the blockers of the scene to be water-tight solids.

We seek a tight overestimate of the PVS as seen from a viewcell so that quick visibility queries with respect to any viewpoint in the viewcell are possible. Given a viewcell, these are the necessary steps:

#### Scene discretization

Rasterize the boundary of scene objects into the discretization of space and determine which voxels of space are completely inside an object and therefore opaque.

#### Blocker extension

 Traverse the discretization of space and find an opaque voxel that is not already hidden. Group this blocker with neighboring opaque voxels to obtain an effective blocker.

#### Shaft construction

Construct a shaft that encompasses the region of space hidden by this blocker as seen from the viewcell.

#### Occlusion tracking

Use the shaft to classify the voxels into partially or completely outside the shaft and fully inside and thus occluded. Take note of occluded voxels.

The major contributions of this approach are a conservative scene discretization that decouples the effectiveness of visibility calculations from how the scene was modeled (i.e. presence of large polygons or convex objects, or number of polygons), and the introduction of blocker extension as a means of both finding efficient blockers and performing effective occluder fusion. Finally, we improve on shafts by observing that 3D shafts can be treated entirely in 2D.

We begin by describing our algorithm in the simple setting of two dimensions and note that this case is already suited to solve visibility queries on scenes such as a 2D floor plan or the map of a city.

### 4 2D Case

Our subdivisions of space are a quadtree in 2D and a 2 1/2D, and an octree in 3D. In anticipation of the extension to 2 1/2D and 3D we will uniformly call a node in the tree a voxel. Its shape is always a (2D or 3D) axis-aligned box.

#### 4.1 Scene Discretization

Our method requires that the interiors of objects can be distinguished from their exteriors. Objects need to have a solid volume. The discretization represents a cube of space containing the scene. All voxels containing a surface are marked as boundary voxels. After this step, boundary voxels completely separate empty regions of space from opaque regions. Next we classify the non-boundary voxels into empty and opaque voxels using the odd-parity rule [12] for point-in-polygon or point-in-closed-shape testing.

We accelerate voxel classification by propagating the voxel status with depth-first seed-filling [22] up to the boundary voxels. Figure 1 shows an example taken from a simple test scene used throughout Section 4. Note that the blockers are not axis-aligned. Such an arrangement would improve the efficiency of the spatial discretization, but is not a requirement of the algorithm.

Our algorithm deals with scenes containing non-solid objects in several ways. If a voxel size is known, such that after marking boundary voxels the empty regions of space form a connected set of voxels, a single call to seed-filling will determine all empty voxels. The opaque voxels are the remaining non-boundary voxels. If some objects have holes or interior faces, the algorithm can still run and use the opaque interior of other objects. Objects with holes

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²Near the surfaces, the spatial hierarchy is subdivided down to a maximum level. This maximizes the number of opaque voxels inside the objects.
have no defined interior and therefore are not used as occluders. Interior faces are ignored by flood-filling only the empty space around objects. Alternatively, degenerate input data can be cleaned up and interior faces can be removed using a method such as the one given by Murali et al. [19].

4.2 Blocker Extension

We recursively traverse the tree until we find an opaque voxel. This is the blocker used with the viewcell to construct the region of occluded space. To maximize occlusion we first extend the blocker. This extension must not hinder the ease of constructing the hidden region, so we require the extension to keep the box-shape of the blocker (see left side of Figure 2). Other opaque voxels are shown in black and will be considered as blockers next.

We extend the blocker along the coordinate axis, which maximizes the angle subtended by the blocker. Extension proceeds on both sides in this direction until there is a non-opaque voxel within the width of the blocker. In the cases where two sides of the blocker are visible from the viewcell, the blocker can additionally be extended into an L-shape as shown in Figure 3. From the viewcell, this L-shape appears exactly the same as the big dashed box enclosing the L-shape that is the blocker’s final extension.

We use two optimizations to quickly find large hidden regions of space. First, we use the blockers in the order from the viewcell outwards; hence, blockers that subtend a wide solid angle compared to their size get used first. Second, we use large blockers in high levels of our spatial data structure first, as these can be expected to occlude large regions of space quickly. Hidden regions are not considered further for blocker selection.

4.3 Blocker Extension into Hidden Space

Despite its simplicity, the idea of extending blockers into adjacent opaque space has not been used in previous approaches. In addition, we make an even stronger point with blocker extension into hidden space, regardless of whether this space is empty or opaque. Extending blockers into hidden regions of space is based on the following observation (see Figure 4).

An observer inside the viewcell is unable to distinguish whether a hidden voxel is opaque or empty. For the sake of finding large occluders for this viewcell, we can assume that the voxel is opaque, and blocker extension can proceed into hidden voxels just as into opaque voxels.

In fact, one can construct different scenes that look exactly the same from within the viewcell by arbitrarily changing hidden parts of the model. One well-known application of this property is the PVS, where all polygons in hidden areas of the scene are removed.
4.4 Shaft Construction and Occlusion Tracking

We construct a shaft around the occluded region from the supporting planes\(^2\) between the viewcell and the blocker. Details are given in the appendix. Our implementation differs from the one by Haines et al.\(^{[16]}\) in that we replace set manipulations on box corners with table lookups.

\(^2\)A supporting plane contains an edge from one object and a vertex from another object, such that both objects lie on the same side of the plane\(^{[4]}\).

Once the shaft has been constructed, a recursive traversal of the spatial data structure flags hidden voxels as occluded in the highest tree node possible. Subtrees outside or inside the shaft are not traversed.

If all the children of a voxel in the spatial data structure are found to be hidden, the parent can be marked as being hidden as well. An exception occurs in the 2 1/2 D case, which will be discussed in Section 6. Propagating visibility up the tree is useful for accelerating traversal of the tree for blocker extension, for marking occluded regions, and for querying occlusion of original objects.

4.5 Querying Occlusion of Scene Objects

Occlusion of the original objects is determined by inserting their bounding boxes into the tree and checking that all the voxels they overlap are hidden. When a bounding hierarchy exists on the input scene — say on the block-, house-, and triangle-level — occlusion queries can be further accelerated by interleaving the traversal of the bounding box hierarchy with the traversal of the tree.

Note that we can also determine the visibility of objects that were not initially inserted into the tree. This allows objects unlikely to cause a lot of occlusion to be ignored when constructing the tree. Also, the visibility status can be determined for moving objects or objects that have been added to the scene.

5 3D Case

Usually visibility algorithms for 2D are difficult to extend to 3D because the number of occlusion boundaries grows from \(O(n^2)\) to \(O(n^3)\) \(^{[10]}\), and because the occlusion boundaries are no longer planar in general. In our case, however, the shaft construction extends to 3D in a straightforward fashion. This is due to our choice of viewcells and blockers as axis-aligned boxes in which case occlusion boundaries remain planar.

5.1 Shafts in 3D

Haines et al.\(^{[16]}\) simplify the construction of a shaft’s plane equations by noting that a shaft around axis-aligned boxes consists entirely of planes, the normals of which have at least one zero coordinate. In addition, a 3D shaft can be more efficiently treated as the intersection of three 2D shafts, namely the shaft’s projections onto the three coordinate planes as shown in Figure 8. A bounding box is then inside the shaft if it is inside each of the three 2D shafts. We ensure that planes orthogonal to the coordinate axes are included only in one 2D shaft.

5.2 Blocker Extension in 3D

In 3D, a blocker must be extended along more than one dimension to subtend a large solid angle. We first extend the blocker along one
Figure 8: A 3D shaft can be treated as the intersection of three 2D shafts (the shaft’s orthographic projection along the coordinate axes).

Figure 9: Blocker extension in 3D.

We have tried to maximize the solid angle subtended by the blocker over different reduction fractions (see second step of Figure 9). We did not observe any noticeable increase in the occlusions identified, but CPU time increased considerably. It is our experience that occluder fusion more than compensates for any suboptimal blocker extension.

Similar to the L-shaped blocker extension in 2D, the blocker is also extended along additionally visible faces as shown in Figure 10. Other than that, occlusion detection in 3D works exactly the same as in 2D: voxels in the tree that are completely inside the shaft of the blocker are marked as occluded.

6 2 1/2D Case

Memory requirements for a 3D octree are sometimes a concern. However, scenes such as terrains or cities can often be dealt with in 2 1/2D. The 2 1/2D quadtree is constructed by recording the height of the highest and lowest points of every primitive falling within a certain voxel (i.e. a square on the ground plane). No ray-casting or seed-filling is necessary. Our tree construction algorithm strictly enforces the 2 1/2D characteristic of the input data set and filters out multiple triangles above a single location on the ground plane. Voxels are occluded if they are inside the shaft up to their maximum height and can be used as an occluder up to their minimum height.

We perform occluder extension the same way as in the 2D case including L-shaped extension; shaft construction is the same as in the 3D case — three 2D shafts are generated. The shaft plane coincident with the ground is ignored. Even though only one shaft in the ground plane and one plane connecting the highest point on the viewcell with the lowest point on the blocker could be used, we found the three 2D shafts to be more effective as they allow easy tracking of occluded height in the 2D projections. We store this height per hidden voxel.
An important difference to the previous two cases of 2D and 3D occlusion detection occurs with the propagation of visibility up the tree. Even if all the children are hidden, the parent is not necessarily hidden everywhere up to its maximum height. Calculating and storing the height up to which a voxel is hidden helps both with visibility propagation up the tree and also with occluder extension, because higher occluders can be extended into a certain voxel.

Figure 11 shows examples of detected occlusion in a terrain model with the maximum tree subdivision of 6, 8 and 10.

7 Applications and Results

We apply occlusion detection to the following rendering algorithms: visibility preprocessing for real-time walkthroughs and shadow-ray culling in ray-tracing. We use the 2 1/2D quadtree to find both viewcells and their PVS in an outdoor city environment. The 3D version is then applied to find the surfaces not receiving direct light from extended light sources in a ray-tracer.

7.1 Visibility Preprocessing for Walkthroughs

Since cities and other outdoor scenes are predominantly 2 1/2D, we use the 2 1/2D quadtree described in Section 6 for occlusion calculations. The model shown in Figure 12 consists of 316,944 triangles that are organized into 665 buildings and 125 blocks complete with streets and sidewalks. Table 1 shows statistics on how long the quadtree takes to build based on the maximum subdivision level in the tree (e.g. subdivision 8 stands for a 256⁴ maximum subdivision). Figure 12 shows the tree portions in blue found to be occluded for one viewcell.

Using a moderate tree subdivision level (up to 8 levels) visibility queries are possible at interactive rates (a few tenths of a second). This includes querying objects in the tree. To avoid this expense of computation at runtime, we pre-compute PVSs for those regions of our model reachable during visual navigation.

Our walkthrough system accepts the navigable space as a set of triangles describing the streets or paths. We first determine the PVS for every triangle in the street mesh by constructing a 3D bounding box around it and marking occluded sections of the model in the quadtree. Then we look up the objects such as buildings, terrain and street portions, trees, cars and people in the quadtree and only add those to the triangle’s PVS that are not fully occluded.

A total of 2,538 triangles in the streets have been automatically grouped into 700 street sections for database paging as shown in Figure 13. By imposing an upper limit on the difference between the size of the triangles’ PVSs in one street section, our greedy merge algorithm limits the amount of overlap seen within each section. The walkthrough system pre-fetches the geometry for adjacent street sections as the user moves around so that exploration is possible without interruption. Such predictive database paging is impossible with online point-visibility methods.

Preprocessing this scene took 55 minutes, the vast majority of which was spent to find the PVS for every viewcell. The remaining time is used for building the tree and grouping viewcells into street sections. The average time for finding the PVS of a triangle is less than a second.

<table>
<thead>
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<th>memory (kB)</th>
<th>time to build (sec)</th>
</tr>
</thead>
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<td>1.902</td>
<td>3.704</td>
</tr>
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<td>9</td>
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</tr>
<tr>
<td>10</td>
<td>472,561</td>
<td>22.683</td>
<td>10.197</td>
</tr>
</tbody>
</table>

Table 1: 2 1/2 D quadtree generation statistics: number of nodes, memory, and build time as a function of the maximum subdivision level in the tree on a MIPS R10k processor running at 250 MHz.
We noted a couple of difficulties in this point-sampled reference solution: narrow gaps between buildings can still be missed and the blocks or buildings visible through these gaps are not reported as visible. Also, in views looking down long straight streets, the sidewalks and streets project to very small areas in screen space and can be missed as well. This supports the need for methods such as the one presented in this paper.

We give the comparison between our PVS and the point-sampled solution in Table 2. Note that the difference is always positive or zero, which demonstrates that our method is conservative.

Finally, Figure 14 shows the difference in drawing time measured on an SGI Infinite Reality system. The left shows results for block-based PVS, the right shows results for building-based PVS compared to IRIS Performer view-frustum culling.

### 7.2 Shadow Ray Acceleration

When ray-tracing complex scenes with many lights, tracing shadow rays and computing object intersections can account for 95% of the rendering time [15]. It is therefore desirable to minimize the number of rays traced. Methods have been developed to accelerate shadow rays for point sources [15, 30], but the work published for extended lights is either approximate [17] or not directly applicable to a ray tracer [25]. Extended lights are preferable, as they cast soft shadows rather than the unnaturally looking sharp shadows caused by point lights.

Our shadow ray acceleration is a generalization of the method of Woo and Amanatides [30] from point light sources to extended light sources. Figure 15 shows an example of the artifacts to be expected if one tries to apply a point-light acceleration technique to an extended light source. The point light causes a sharp shadow which is contained in the region of penumbra of an area light source at the same position. A point-light acceleration algorithm falsely identifies regions of the penumbra as in shadow and pronounced boundaries appear in the umbra where there should be a continuous light-intensity variation.

The acceleration technique uses the full 3D version of our algorithm with space represented as an octree, as described in Section 5. We find the bounding box for every light source in the model and use it as a viewcell. For every light source we copy and keep the visible portion of the octree\(^1\). In the case of many light sources, memory consumption is a concern, and only a specific number of top levels in the tree are copied with only a small increase in the number of occlusions that are not detected (as shown in the results below). Our representation of the octree uses eight bytes per node.

As the ray-tracer renders the scene, every light’s octree is queried to determine whether the current sample point is potentially visible to the light. Shadow rays need only to be cast for potentially visible points. The top of Figure 16 shows a view of a city block at night with ten street lights around it. Below is a false-color image of the same block from above where every pixel is given a color based on which light sources would be queried with shadow rays. All

---

<table>
<thead>
<tr>
<th>block-based</th>
<th>total: 125 blocks (about 2,500 tris on avg)</th>
<th>our method</th>
<th>point samples</th>
<th>difference</th>
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<tbody>
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<td>avg</td>
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<table>
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<td>33.99</td>
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</tbody>
</table>

Table 2: Comparison of PVS sizes for block-based (125 blocks) and building-based (665 buildings) PVS computation. Going from block-based to building-based PVSs reduced the average difference between the two methods from 10.91% to 2.98% of the complete model.

\(^1\)Figure 19 shows that these copies require memory comparable to the initial octree.
images in this section are rendered with one sample per pixel, and global illumination taken into account using stochastic sampling optimized with irradiance gradient caching [29]. The ray tracer uses hierarchical grids as the general acceleration data structure. Preprocessing took 53.3 seconds on a Pentium II 400MHz processor, and the time to render this image was reduced from about 250 seconds to 100 seconds (a 60% saving). This is particularly advantageous for animation sequences with static lighting, where the preprocessing is amortized over the full set of frames.

Figure 17 shows more complex scenes: a gallery with paintings and people (17,701 triangles and 23 light sources) and a residential area (616,509 triangles, 459 light sources). The bars on the left of Figures 18 and 19 give tree construction time and initial tree memory usage respectively as a function of the maximum octree subdivision level. The right graph in Figure 18 plots rendering time as a function of the number of levels kept in the octree per light. The right graph in Figure 19 gives the memory requirements for the octree copies. The original tree is no longer needed during rendering.

By considering both charts together, one observes that seven levels in the octree are not sufficient to accurately capture the occluders in the gallery scene (eight in the residential area scene). However, there is no longer a substantial difference between the rendering times using a $256^3$ octree or a $512^3$ octree ($512^3$ or $1024^3$ for the residential area scene). It is surprising that three or more levels can be discarded from the light source octree without paying a significant price in the number of occlusions missed. However, the savings in memory are quite substantial.

Finally, Figure 20 shows the effectiveness of the method by giving the percentage of shadow rays successfully culled and the percentage of traced shadow rays, which were found to intersect geometry. This is the percentage of rays that was not reported as occluded even though the sample point is hidden from the light source. Note how this number decreases as the octree resolution increases. In the case of the residential area, the percentage of rays blocked although not reported as such remains quite high, because the lamp geometry was not inserted into the octree and, therefore, sample points on the facades at a height above the light could not be found to be in shadow. The results can be summarized as follows: with a doubled memory consumption rendering is accelerated by a factor of three for the gallery scene and by a factor of four for the residential area scene.
such as kd-trees or more sophisticated boundary nodes to improve the effectiveness of the method. We also want to investigate the success of blocker extension in other previously proposed visibility methods. Moreover, by rasterizing freeform patches or constructive solid geometry our visibility algorithm could be extended to these modeling approaches.

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References


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Appendix

In 2D the shaft between two boxes is delimited by lines through the corners of the boxes and a subset of the blocker faces. Table 3 lists the box corners that need to be connected. Figure 21 gives a pictorial overview of the cases.

<table>
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<td>1.3</td>
<td>-</td>
<td>2.0</td>
<td>all</td>
</tr>
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<td>2.1</td>
<td>2.3</td>
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<td>Y: 3</td>
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<td>all</td>
<td>3.1</td>
<td>-</td>
</tr>
</tbody>
</table>

Table 3: Box corners to be connected based on the relative position of the boxes. Cases where four connections must be made are marked “all”, but are only relevant for the 2 1/2D and 3D extensions if viewcells are limited to empty space.

Figure 21: First row: cases of mutual positions between blocker and viewcell along the X-axis. The shafts are shown in grey. The rest of the figure gives a pictorial impression of the contents of Table 3.