

# Package ‘geometry’

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**License** GPL (>= 3)

**Title** Mesh Generation and Surface Tessellation

**Description** Makes the 'Qhull' library <<http://www.qhull.org>> available in R, in a similar manner as in Octave and MATLAB. Qhull computes convex hulls, Delaunay triangulations, halfspace intersections about a point, Voronoi diagrams, furthest-site Delaunay triangulations, and furthest-site Voronoi diagrams. It runs in 2D, 3D, 4D, and higher dimensions. It implements the Quickhull algorithm for computing the convex hull. Qhull does not support constrained Delaunay triangulations, or mesh generation of non-convex objects, but the package does include some R functions that allow for this.

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## Contents

bary2cart . . . . .	3
cart2bary . . . . .	4
cart2pol . . . . .	5
cart2sph . . . . .	6
convhulln . . . . .	7
delaunayn . . . . .	9
distmesh2d . . . . .	11
distmeshnd . . . . .	13
dot . . . . .	15
entry.value . . . . .	16
extprod3d . . . . .	17
feasible.point . . . . .	17
halfspacen . . . . .	18
inhulln . . . . .	19
intersectn . . . . .	20
matmax . . . . .	21
mesh.dcircle . . . . .	22
mesh.diff . . . . .	23
mesh.drectangle . . . . .	24
mesh.dsphere . . . . .	25
mesh.hunif . . . . .	26
pol2cart . . . . .	26
polyarea . . . . .	27
rbox . . . . .	28
sph2cart . . . . .	28
surf.tri . . . . .	29
tetramesh . . . . .	30
to.mesh3d . . . . .	31
trimesh . . . . .	32
tsearch . . . . .	33
tsearchn . . . . .	34
Unique . . . . .	35

**Index**

**36**

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**bary2cart***Conversion of Barycentric to Cartesian coordinates*

---

**Description**

Given the barycentric coordinates of one or more points with respect to a simplex, compute the Cartesian coordinates of these points.

**Usage**

```
bary2cart(X, Beta)
```

**Arguments**

X	Reference simplex in $N$ dimensions represented by a $N + 1$ -by- $N$ matrix
Beta	$M$ points in barycentric coordinates with respect to the simplex X represented by a $M$ -by- $N + 1$ matrix

**Value**

$M$ -by- $N$  matrix in which each row is the Cartesian coordinates of corresponding row of Beta

**Author(s)**

David Sterratt

**See Also**

[cart2bary](#)

**Examples**

```
## Define simplex in 2D (i.e. a triangle)
X <- rbind(c(0, 0),
           c(0, 1),
           c(1, 0))
## Cartesian coordinates of points
beta <- rbind(c(0, 0.5, 0.5),
             c(0.1, 0.8, 0.1))
## Plot triangle and points
trimesh(rbind(1:3), X)
text(X[,1], X[,2], 1:3) # Label vertices
P <- bary2cart(X, beta)
points(P)
```

---

cart2bary

*Conversion of Cartesian to Barycentric coordinates.*


---

**Description**

Given the Cartesian coordinates of one or more points, compute the barycentric coordinates of these points with respect to a simplex.

**Usage**

```
cart2bary(X, P)
```

**Arguments**

X                      Reference simplex in  $N$  dimensions represented by a  $N + 1$ -by- $N$  matrix  
P                         $M$ -by- $N$  matrix in which each row is the Cartesian coordinates of a point.

**Details**

Given a reference simplex in  $N$  dimensions represented by a  $N + 1$ -by- $N$  matrix an arbitrary point  $P$  in Cartesian coordinates, represented by a 1-by- $N$  row vector, can be written as

$$P = \beta X$$

where  $\beta$  is an  $N + 1$  vector of the barycentric coordinates. A criterion on  $\beta$  is that

$$\sum_i \beta_i = 1$$

Now partition the simplex into its first  $N$  rows  $X_N$  and its  $N + 1$ th row  $X_{N+1}$ . Partition the barycentric coordinates into the first  $N$  columns  $\beta_N$  and the  $N + 1$ th column  $\beta_{N+1}$ . This allows us to write

$$P_{N+1} - X_{N+1} = \beta_N X_N + \beta_{N+1} X_{N+1} - X_{N+1}$$

which can be written

$$P_{N+1} - X_{N+1} = \beta_N (X_N - 1_N X_{N+1})$$

where  $1_N$  is an  $N$ -by-1 matrix of ones. We can then solve for  $\beta_N$ :

$$\beta_N = (P_{N+1} - X_{N+1})(X_N - 1_N X_{N+1})^{-1}$$

and compute

$$\beta_{N+1} = 1 - \sum_{i=1}^N \beta_i$$

This can be generalised for multiple values of  $P$ , one per row.

**Value**

$M$ -by- $N + 1$  matrix in which each row is the barycentric coordinates of corresponding row of  $P$ . If the simplex is degenerate a warning is issued and the function returns NULL.

**Note**

Based on the Octave function by David Bateman.

**Author(s)**

David Sterratt

**See Also**

[bary2cart](#)

**Examples**

```
## Define simplex in 2D (i.e. a triangle)
X <- rbind(c(0, 0),
           c(0, 1),
           c(1, 0))
## Cartesian coordinates of points
P <- rbind(c(0.5, 0.5),
           c(0.1, 0.8))
## Plot triangle and points
trimesh(rbind(1:3), X)
text(X[,1], X[,2], 1:3) # Label vertices
points(P)
cart2bary(X, P)
```

---

cart2pol

*Transform Cartesian coordinates to polar or cylindrical coordinates.*

---

**Description**

The inputs x, y (, and z) must be the same shape, or scalar. If called with a single matrix argument then each row of C represents the Cartesian coordinate (x, y (, z)).

**Usage**

```
cart2pol(x, y = NULL, z = NULL)
```

**Arguments**

x	x-coordinates or matrix with three columns
y	y-coordinates (optional, if x) is a matrix
z	z-coordinates (optional, if x) is a matrix

**Value**

A matrix P where each row represents one polar/(cylindrical) coordinate (theta, r, (, z)).

**Author(s)**

Kai Habel  
David Sterratt

**See Also**

[pol2cart](#), [cart2sph](#), [sph2cart](#)

---

cart2sph

*Transform Cartesian to spherical coordinates*

---

**Description**

If called with a single matrix argument then each row of `c` represents the Cartesian coordinate (x, y, z).

**Usage**

```
cart2sph(x, y = NULL, z = NULL)
```

**Arguments**

x	x-coordinates or matrix with three columns
y	y-coordinates (optional, if x) is a matrix
z	z-coordinates (optional, if x) is a matrix

**Value**

Matrix with columns:

theta	the angle relative to the positive x-axis
phi	the angle relative to the xy-plane
r	the distance to the origin (0, 0, 0)

**Author(s)**

Kai Habel  
David Sterratt

**See Also**

[sph2cart](#), [cart2pol](#), [pol2cart](#)

convhulln

*Compute smallest convex hull that encloses a set of points***Description**

Returns information about the smallest convex complex of a set of input points in  $N$ -dimensional space (the convex hull of the points). By default, indices to points forming the facets of the hull are returned; optionally normals to the facets and the generalised surface area and volume can be returned. This function interfaces the [Qhull](#) library.

**Usage**

```
convhulln(
  p,
  options = "Tv",
  output.options = NULL,
  return.non.triangulated.facets = FALSE
)
```

**Arguments**

**p** An  $M$ -by- $N$  matrix. The rows of **p** represent  $M$  points in  $N$ -dimensional space.

**options** String containing extra options for the underlying Qhull command; see details below and Qhull documentation at [../doc/qhull/html/qconvex.html#synopsis](#).

**output.options** String containing Qhull options to generate extra output. Currently **n** (normals) and **FA** (generalised areas and volumes) are supported; see ‘Value’ for details. If **output.options** is **TRUE**, select all supported options.

**return.non.triangulated.facets** logical defining whether the output facets should be triangulated; **FALSE** by default.

**Value**

By default (**return.non.triangulated.facets** is **FALSE**), return an  $M$ -by- $N$  matrix in which each row contains the indices of the points in **p** forming an  $N - 1$ -dimensional facet. e.g In 3 dimensions, there are 3 indices in each row describing the vertices of 2-dimensional triangles.

If **return.non.triangulated.facets** is **TRUE** then the number of columns equals the maximum number of vertices in a facet, and each row defines a polygon corresponding to a facet of the convex hull with its vertices followed by NAs until the end of the row.

If the **output.options** or **options** argument contains **FA** or **n**, return a list with class **convhulln** comprising the named elements:

**p** The points passed to **convhulln**

**hull** The convex hull, represented as a matrix indexing **p**, as described above

area If FA is specified, the generalised area of the hull. This is the surface area of a 3D hull or the length of the perimeter of a 2D hull. See [../doc/qhull/html/qh-optf.html#FA](http://doc/qhull/html/qh-optf.html#FA).

vol If FA is specified, the generalised volume of the hull. This is volume of a 3D hull or the area of a 2D hull. See [../doc/qhull/html/qh-optf.html#FA](http://doc/qhull/html/qh-optf.html#FA).

normals If n is specified, this is a matrix hyperplane normals with offsets. See [../doc/qhull/html/qh-opto.html#n](http://doc/qhull/html/qh-opto.html#n).

### Note

This function was originally a port of the **Octave** convhulln function written by Kai Habel.

See further notes in [deelaunayn](#).

### Author(s)

Raoul Grasman, Robert B. Gramacy, Pavlo Mozharovskyi and David Sterratt <david.c.sterratt@ed.ac.uk>

### References

*Barber, C.B., Dobkin, D.P., and Huhdanpaa, H.T., "The Quickhull algorithm for convex hulls,"*  
ACM Trans. on Mathematical Software, Dec 1996.

<http://www.qhull.org>

### See Also

[intersectn](#), [deelaunayn](#), [surf.tri](#), [convex.hull](#)

### Examples

```
## Points in a sphere
ps <- matrix(rnorm(3000), ncol=3)
ps <- sqrt(3)*ps/drop(sqrt((ps^2) %*% rep(1, 3)))
ts.surf <- t(convhulln(ps)) # see the qhull documentations for the options
## Not run:
rgl::triangles3d(ps[ts.surf,1],ps[ts.surf,2],ps[ts.surf,3],col="blue",alpha=.2)
for(i in 1:(8*360)) rgl::view3d(i/8)

## End(Not run)

## Square
pq <- rbox(0, C=0.5, D=2)
# Return indices only
convhulln(pq)
# Return convhulln object with normals, generalised area and volume
ch <- convhulln(pq, output.options=TRUE)
plot(ch)

## Cube
pc <- rbox(0, C=0.5, D=3)
# Return indices of triangles on surface
convhulln(pc)
```



```
# Return indices of squares on surface
convhulln(pc, return.non.triangulated.facets=TRUE)
```

---

delaunayn

*Delaunay triangulation in N dimensions*


---

## Description

The Delaunay triangulation is a tessellation of the convex hull of the points such that no  $N$ -sphere defined by the  $N$ -triangles contains any other points from the set.

## Usage

```
delaunayn(p, options = NULL, output.options = NULL, full = FALSE)
```

## Arguments

p	An $M$ -by- $N$ matrix whose rows represent $M$ points in $N$ -dimensional space.
options	String containing extra control options for the underlying Qhull command; see the Qhull documentation ( <a href="http://doc/qhull/html/qdelaun.html">./doc/qhull/html/qdelaun.html</a> ) for the available options. The Qbb option is always passed to Qhull. The remaining default options are Qcc Qc Qt Qz for $N < 4$ and Qcc Qc Qt Qx for $N \geq 4$ . If neither of the QJ or Qt options are supplied, the Qt option is passed to Qhull. The Qt option ensures all Delaunay regions are simplicial (e.g., triangles in 2D). See <a href="http://doc/qhull/html/qdelaun.html">./doc/qhull/html/qdelaun.html</a> for more details. Contrary to the Qhull documentation, no degenerate (zero area) regions are returned with the Qt option since the R function removes them from the triangulation. <i>If options is specified, the default options are overridden.</i> It is recommended to use output.options for options controlling the outputs.
output.options	String containing Qhull options to control output. Currently Fn (neighbours) and Fa (areas) are supported. Causes an object of return value for details. If output.options is TRUE, select all supported options.
full	Deprecated and will be removed in a future release. Adds options Fa and Fn.

## Value

If output.options is NULL (the default), return the Delaunay triangulation as a matrix with  $M$  rows and  $N + 1$  columns in which each row contains a set of indices to the input points p. Thus each row describes a simplex of dimension  $N$ , e.g. a triangle in 2D or a tetrahedron in 3D.

If the output.options argument is TRUE or is a string containing Fn or Fa, return a list with class delaunayn comprising the named elements:

tri The Delaunay triangulation described above

areas If TRUE or if Fa is specified, an  $M$ -dimensional vector containing the generalised area of each simplex (e.g. in 2D the areas of triangles; in 3D the volumes of tetrahedra). See [./doc/qhull/html/qh-optf.html#Fa](http://doc/qhull/html/qh-optf.html#Fa).

`neighbours` If TRUE or if `Fn` is specified, a list of neighbours of each simplex. Note that a negative number corresponds to "facet" (= "edge" in 2D or "face" in 3D) that has no neighbour, as will be the case for some simplices on the boundary of the triangulation. See [../doc/qhull/html/qh-optf.html#Fn](http://www.qhull.org/html/qh-optf.html#Fn)

### Note

This function interfaces the Qhull library and is a port from Octave (<https://octave.org/>) to R. Qhull computes convex hulls, Delaunay triangulations, halfspace intersections about a point, Voronoi diagrams, furthest-site Delaunay triangulations, and furthest-site Voronoi diagrams. It runs in 2D, 3D, 4D, and higher dimensions. It implements the Quickhull algorithm for computing the convex hull. Qhull handles round-off errors from floating point arithmetic. It computes volumes, surface areas, and approximations to the convex hull. See the Qhull documentation included in this distribution (the doc directory [../doc/qhull/index.html](http://www.qhull.org/html/qh-optf.html#Fn)).

Qhull does not support constrained Delaunay triangulations, triangulation of non-convex surfaces, mesh generation of non-convex objects, or medium-sized inputs in 9D and higher. A rudimentary algorithm for mesh generation in non-convex regions using Delaunay triangulation is implemented in [distmesh2d](#) (currently only 2D).

### Author(s)

Raoul Grasman and Robert B. Gramacy; based on the corresponding Octave sources of Kai Habel.

### References

*Barber, C.B., Dobkin, D.P., and Huhdanpaa, H.T., "The Quickhull algorithm for convex hulls,"* ACM Trans. on Mathematical Software, Dec 1996.

<http://www.qhull.org>

### See Also

[tri.mesh](#), [convhulln](#), [surf.tri](#), [distmesh2d](#)

### Examples

```
# example delaunayn
d <- c(-1,1)
pc <- as.matrix(rbind(expand.grid(d,d,d),0))
tc <- delaunayn(pc)

# example tetramesh
## Not run:
rgl::view3d(60)
rgl::light3d(120,60)
tetramesh(tc,pc, alpha=0.9)

## End(Not run)

tc1 <- delaunayn(pc, output.options="Fa")
## sum of generalised areas is total volume of cube
```

```
sum(tc1$areas)
```

---

 distmesh2d

*A simple mesh generator for non-convex regions*


---

## Description

An unstructured simplex requires a choice of mesh points (vertex nodes) and a triangulation. This is a simple and short algorithm that improves the quality of a mesh by relocating the mesh points according to a relaxation scheme of forces in a truss structure. The topology of the truss is reset using Delaunay triangulation. A (sufficiently smooth) user supplied signed distance function (fd) indicates if a given node is inside or outside the region. Points outside the region are projected back to the boundary.

## Usage

```
distmesh2d(
  fd,
  fh,
  h0,
  bbox,
  p = NULL,
  pfix = array(0, dim = c(0, 2)),
  ...,
  dptol = 0.001,
  ttol = 0.1,
  Fscale = 1.2,
  deltat = 0.2,
  geps = 0.001 * h0,
  deps = sqrt(.Machine$double.eps) * h0,
  maxiter = 1000,
  plot = TRUE
)
```

## Arguments

fd	Vectorized signed distance function, for example <a href="#">mesh.dcircle</a> or <a href="#">mesh.diff</a> , accepting an n-by-2 matrix, where n is arbitrary, as the first argument.
fh	Vectorized function, for example <a href="#">mesh.hunif</a> , that returns desired edge length as a function of position. Accepts an n-by-2 matrix, where n is arbitrary, as its first argument.
h0	Initial distance between mesh nodes. (Ignored if p is supplied)
bbox	Bounding box <code>cbind(c(xmin,xmax), c(ymin,ymax))</code>
p	An n-by-2 matrix. The rows of p represent locations of starting mesh nodes.
pfix	nfix-by-2 matrix with fixed node positions.

...	parameters to be passed to fd and/or fh
dptol	Algorithm stops when all node movements are smaller than dptol
ttol	Controls how far the points can move (relatively) before a retriangulation with <a href="#">delaunayn</a> .
Fscale	“Internal pressure” in the edges.
deltat	Size of the time step in Euler’s method.
geps	Tolerance in the geometry evaluations.
deps	Stepsize $\Delta x$ in numerical derivative computation for distance function.
maxiter	Maximum iterations.
plot	logical. If TRUE (default), the mesh is plotted as it is generated.

### Details

This is an implementation of original Matlab software of Per-Olof Persson.

Excerpt (modified) from the reference below:

‘The algorithm is based on a mechanical analogy between a triangular mesh and a 2D truss structure. In the physical model, the edges of the Delaunay triangles of a set of points correspond to bars of a truss. Each bar has a force-displacement relationship  $f(\ell, \ell_0)$  depending on its current length  $\ell$  and its unextended length  $\ell_0$ .’

‘External forces on the structure come at the boundaries, on which external forces have normal orientations. These external forces are just large enough to prevent nodes from moving outside the boundary. The position of the nodes are the unknowns, and are found by solving for a static force equilibrium. The hope is that (when fh = function(p) return(rep(1, nrow(p))))), the lengths of all the bars at equilibrium will be nearly equal, giving a well-shaped triangular mesh.’

See the references below for all details. Also, see the comments in the source file.

### Value

n-by-2 matrix with node positions.

### Wishlist

- Implement in C/Fortran
- Implement an nD version as provided in the Matlab package
- Translate other functions of the Matlab package

### Author(s)

Raoul Grasman

### References

<http://persson.berkeley.edu/distmesh/>

*P.-O. Persson, G. Strang, A Simple Mesh Generator in MATLAB. SIAM Review, Volume 46 (2), pp. 329-345, June 2004*

**See Also**

[tri.mesh](#), [delaunayn](#), [mesh.dcircle](#), [mesh.drectangle](#), [mesh.diff](#), [mesh.union](#), [mesh.intersect](#)

**Examples**

```
# examples distmesh2d
fd <- function(p, ...) sqrt((p^2)%*%c(1,1)) - 1
  # also predefined as `mesh.dcircle`
fh <- function(p,...) rep(1,nrow(p))
bbox <- matrix(c(-1,1,-1,1),2,2)
p <- distmesh2d(fd,fh,0.2,bbox, maxiter=100)
  # this may take a while:
  # press Esc to get result of current iteration

# example with non-convex region
fd <- function(p, ...) mesh.diff(p , mesh.drectangle, mesh.dcircle, radius=.3)
  # fd defines difference of square and circle

p <- distmesh2d(fd,fh,0.05,bbox,radius=0.3,maxiter=4)
p <- distmesh2d(fd,fh,0.05,bbox,radius=0.3, maxiter=10)
  # continue on previous mesh
```

---

 distmeshnd

---

*A simple mesh generator for non-convex regions in n-D space*


---

**Description**

An unstructured simplex requires a choice of mesh points (vertex nodes) and a triangulation. This is a simple and short algorithm that improves the quality of a mesh by relocating the mesh points according to a relaxation scheme of forces in a truss structure. The topology of the truss is reset using Delaunay triangulation. A (sufficiently smooth) user supplied signed distance function (fd) indicates if a given node is inside or outside the region. Points outside the region are projected back to the boundary.

**Usage**

```
distmeshnd(
  fdist,
  fh,
  h,
  box,
  pfix = array(dim = c(0, ncol(box))),
  ...,
  ptol = 0.001,
  ttol = 0.1,
  deltat = 0.1,
  geps = 0.1 * h,
  deps = sqrt(.Machine$double.eps) * h
)
```

**Arguments**

<code>fdist</code>	Vectorized signed distance function, for example <code>mesh.dsphere</code> , accepting an $m$ -by- $n$ matrix, where $m$ is arbitrary, as the first argument.
<code>fh</code>	Vectorized function, for example <code>mesh.hunif</code> , that returns desired edge length as a function of position. Accepts an $m$ -by- $n$ matrix, where $n$ is arbitrary, as its first argument.
<code>h</code>	Initial distance between mesh nodes.
<code>box</code>	2-by- $n$ matrix that specifies the bounding box. (See <code>distmesh2d</code> for an example.)
<code>pfix</code>	$n$ fix-by-2 matrix with fixed node positions.
<code>...</code>	parameters that are passed to <code>fdist</code> and <code>fh</code>
<code>ptol</code>	Algorithm stops when all node movements are smaller than <code>dptol</code>
<code>ttol</code>	Controls how far the points can move (relatively) before a retriangulation with <code>de launayn</code> .
<code>deltat</code>	Size of the time step in Euler's method.
<code>geps</code>	Tolerance in the geometry evaluations.
<code>deps</code>	Stepsize $\Delta x$ in numerical derivative computation for distance function.

**Details**

This is an implementation of original Matlab software of Per-Olof Persson.

Excerpt (modified) from the reference below:

'The algorithm is based on a mechanical analogy between a triangular mesh and a  $n$ -D truss structure. In the physical model, the edges of the Delaunay triangles of a set of points correspond to bars of a truss. Each bar has a force-displacement relationship  $f(\ell, \ell_0)$  depending on its current length  $\ell$  and its unextended length  $\ell_0$ .'

'External forces on the structure come at the boundaries, on which external forces have normal orientations. These external forces are just large enough to prevent nodes from moving outside the boundary. The position of the nodes are the unknowns, and are found by solving for a static force equilibrium. The hope is that (when `fh = function(p) return(rep(1, nrow(p)))`), the lengths of all the bars at equilibrium will be nearly equal, giving a well-shaped triangular mesh.'

See the references below for all details. Also, see the comments in the source file of `distmesh2d`.

**Value**

$m$ -by- $n$  matrix with node positions.

**Wishlist**

- Implement in C/Fortran
- Translate other functions of the Matlab package

**Author(s)**

Raoul Grasman; translated from original Matlab sources of Per-Olof Persson.

## References

<http://persson.berkeley.edu/distmesh/>

P.-O. Persson, G. Strang, *A Simple Mesh Generator in MATLAB*. *SIAM Review*, Volume 46 (2), pp. 329-345, June 2004

## See Also

[distmesh2d](#), [tri.mesh](#), [delaunayn](#), [mesh.dsphere](#), [mesh.hunif](#),  
[mesh.diff](#), [mesh.union](#), [mesh.intersect](#)

## Examples

```
## Not run:
# examples distmeshnd
require(rgl)

fd = function(p, ...) sqrt((p^2)%*%c(1,1,1)) - 1
    # also predefined as `mesh.dsphere`
fh = function(p, ...) rep(1,nrow(p))
    # also predefined as `mesh.hunif`
bbox = matrix(c(-1,1),2,3)
p = distmeshnd(fd,fh,0.2,bbox, maxiter=100)
    # this may take a while:
    # press Esc to get result of current iteration

## End(Not run)
```

---

dot

*Compute the dot product of two vectors*

---

## Description

If  $x$  and  $y$  are matrices, calculate the dot-product along the first non-singleton dimension. If the optional argument  $d$  is given, calculate the dot-product along this dimension.

## Usage

```
dot(x, y, d = NULL)
```

## Arguments

$x$	Matrix of vectors
$y$	Matrix of vectors
$d$	Dimension along which to calculate the dot product

**Value**

Vector with length of dth dimension

**Author(s)**

David Sterratt

---

entry.value

*Retrieve or set a list of array element values*

---

**Description**

entry.value retrieves or sets the values in an array a at the positions indicated by the rows of a matrix idx.

**Usage**

```
entry.value(a, idx)
```

**Arguments**

a	An array.
idx	Numerical matrix with the same number of columns as the number of dimensions of a. Each row indices a cell in a of which the value is to be retrieved or set.
value	An array of length nrow(idx).

**Value**

entry.value(a, idx) returns a vector of values at the indicated cells. entry.value(a, idx) <- val changes the indicated cells of a to val.

**Author(s)**

Raoul Grasman

**Examples**

```
a = array(1:(4^4), c(4,4,4,4))
entry.value(a, cbind(1:4, 1:4, 1:4, 1:4))
entry.value(a, cbind(1:4, 1:4, 1:4, 1:4)) <- 0

entry.value(a, as.matrix(expand.grid(1:4, 1:4, 1:4, 1:4)))
# same as `c(a[1:4, 1:4, 1:4, 1:4])` which is same as `c(a)`
```



---

extprod3d                      *Compute external- or 'cross'- product of 3D vectors.*

---

### Description

Computes the external product

$$(x_2y_3 - x_3y_2, x_3y_1 - x_1y_3, x_1y_2 - x_2y_1)$$

of the 3D vectors in **x** and **y**.

### Usage

```
extprod3d(x, y, drop = TRUE)
```

### Arguments

x	n-by-3 matrix. Each row is one <b>x</b> -vector
y	n-by-3 matrix. Each row is one <b>y</b> -vector
drop	logical. If TRUE and if the inputs are one row matrices or vectors, then delete the dimensions of the array returned.

### Value

If n is greater than 1 or drop is FALSE, n-by-3 matrix; if n is 1 and drop is TRUE, a vector of length 3.

### Author(s)

Raoul Grasman

### See Also

[drop](#)

---

feasible.point                      *Find point in intersection of convex hulls*

---

### Description

Find point that lies somewhere in interesction of two convex hulls. If such a point does not exist, return NA. The feasible point is found using a linear program similar to the one suggested at [.. /doc/qhull/html/qhalf.html#notes](http://doc/qhull/html/qhalf.html#notes)

### Usage

```
feasible.point(ch1, ch2, tol = 0)
```

**Arguments**

ch1	First convex hull with normals
ch2	Second convex hull with normals
tol	The point must be at least this far within the facets of both convex hulls

---

halfspacen

---

*Compute halfspace intersection about a point*


---

**Description**

Compute halfspace intersection about a point

**Usage**

```
halfspacen(p, fp, options = "Tv")
```

**Arguments**

p	An $M$ -by- $N+1$ matrix. Each row of p represents a halfspace by a $N$ -dimensional normal to a hyperplane and the offset of the hyperplane.
fp	A “feasible” point that is within the space contained within all the halfspaces.
options	String containing extra options, separated by spaces, for the underlying Qhull command; see Qhull documentation at <a href="http://www.qhull.org/doc/qhull/html/qhalf.html">../doc/qhull/html/qhalf.html</a> .

**Value**

A  $N$ -column matrix containing the intersection points of the hyperplanes [../doc/qhull/html/qhalf.html](http://www.qhull.org/doc/qhull/html/qhalf.html).

**Note**

halfspacen was introduced in geometry 0.4.0, and is still under development. It is worth checking results for unexpected behaviour.

**Author(s)**

David Sterratt

**References**

Barber, C.B., Dobkin, D.P., and Huhdanpaa, H.T., “The Quickhull algorithm for convex hulls,” ACM Trans. on Mathematical Software, Dec 1996.

<http://www.qhull.org>

**See Also**

[convhulln](#)

## Examples

```
p <- rbox(0, C=0.5) # Generate points on a unit cube centered around the origin
ch <- convhulln(p, "n") # Generate convex hull, including normals to facets, with "n" option
# Intersections of half planes
# These points should be the same as the original points
pn <- halfspacen(ch$normals, c(0, 0, 0))
```

---

inhulln	<i>Test if points lie in convex hull</i>
---------	--

---

## Description

Tests if a set of points lies within a convex hull, returning a boolean vector in which each element is TRUE if the corresponding point lies within the hull and FALSE if it lies outwith the hull or on one of its facets.

## Usage

```
inhulln(ch, p)
```

## Arguments

ch	Convex hull produced using <a href="#">convhulln</a>
p	An $M$ -by- $N$ matrix of points to test. The rows of $p$ represent $M$ points in $N$ -dimensional space.

## Value

A boolean vector with  $M$  elements

## Note

`inhulln` was introduced in `geometry 0.4.0`, and is still under development. It is worth checking results for unexpected behaviour.

## Author(s)

David Sterratt

## See Also

[convhulln](#), `point.in.polygon` in **sp**

**Examples**

```

p <- cbind(c(-1, -1, 1), c(-1, 1, -1))
ch <- convhulln(p)
## First point should be in the hull; last two outside
inhulln(ch, rbind(c(-0.5, -0.5),
                  c( 1 , 1),
                  c(10 , 0)))

## Test hypercube
p <- rbox(D=4, B=1)
ch <- convhulln(p)
tp <- cbind(seq(-1.9, 1.9, by=0.2), 0, 0, 0)
pin <- inhulln(ch, tp)
## Points on x-axis should be in box only betw,een -1 and 1
pin == (tp[,1] < 1 & tp[,1] > -1)

```

---

intersectn

---

*Compute convex hull of intersection of two sets of points*


---

**Description**

Compute convex hull of intersection of two sets of points

**Usage**

```

intersectn(
  ps1,
  ps2,
  tol = 0,
  return.chs = TRUE,
  options = "Tv",
  fp = NULL,
  autoscale = FALSE
)

```

**Arguments**

ps1	First set of points
ps2	Second set of points
tol	Tolerance used to determine if a feasible point lies within the convex hulls of both points and to round off the points generated by the halfspace intersection, which sometimes produces points very close together.
return.chs	If TRUE (default) return the convex hulls of the first and second sets of points, as well as the convex hull of the intersection.
options	Options passed to <a href="#">halfspacen</a> . By default this is Tv.

fp	Coordinates of feasible point, i.e. a point known to lie in the hulls of ps1 and ps2. The feasible point is required for <a href="#">halfspacen</a> to find the intersection. <code>intersectn</code> tries to find the feasible point automatically using the linear program in <a href="#">feasible.point</a> , but currently the linear program fails on some examples where there is an obvious solution. This option overrides the automatic search for a feasible point
autoscale	<i>Experimental in v0.4.2</i> Automatically scale the points to lie in a sensible numeric range. May help to correct some numerical issues.

**Value**

List containing named elements: `ch1`, the convex hull of the first set of points, with volumes, areas and normals (see [convhulln](#); `ch2`, the convex hull of the first set of points, with volumes, areas and normals; `ps`, the intersection points of convex hulls `ch1` and `ch2`; and `ch`, the convex hull of the intersection points, with volumes, areas and normals.

**Note**

`intersectn` was introduced in `geometry 0.4.0`, and is still under development. It is worth checking results for unexpected behaviour.

**Author(s)**

David Sterratt

**See Also**

[convhulln](#), [halfspacen](#), [inhulln](#), [feasible.point](#)

**Examples**

```
# Two overlapping boxes
ps1 <- rbox(0, C=0.5)
ps2 <- rbox(0, C=0.5) + 0.5
out <- intersectn(ps1, ps2)
message("Volume of 1st convex hull: ", out$ch1$vol)
message("Volume of 2nd convex hull: ", out$ch2$vol)
message("Volume of intersection convex hull: ", out$ch$vol)
```

**Description**

Compute maximum or minimum of each row, or sort each row of a matrix, or a set of (equal length) vectors.

**Usage**

```
matmax(...)
```

**Arguments**

...                   A numeric matrix or a set of numeric vectors (that are column-wise bind together into a matrix with cbind).

**Value**

matmin and matmax return a vector of length nrow(cbind(...)). matsort returns a matrix of dimension dim(cbind(...)) with in each row of cbind(...) sorted. matsort(x) is a lot faster than, e.g., t(apply(x,1,sort)), if x is tall (i.e., nrow(x)>ncol(x) and ncol(x)<30. If ncol(x)>30 then matsort simply calls 't(apply(x,1,sort))'. matorder returns a permutation which rearranges its first argument into ascending order, breaking ties by further arguments.

**Author(s)**

Raoul Grasman

**Examples**

```
example(Unique)
```

---

```
mesh.dcircle
```

*Circle distance function*

---

**Description**

Signed distance from points p to boundary of circle to allow easy definition of regions in [distmesh2d](#).

**Usage**

```
mesh.dcircle(p, radius = 1, ...)
```

**Arguments**

p                    A matrix with 2 columns (3 in mesh.dsphere), each row representing a point in the plane.

radius               radius of circle

...                   additional arguments (not used)

**Value**

A vector of length nrow(p) containing the signed distances to the circle

**Author(s)**

Raoul Grasman; translated from original Matlab sources of Per-Olof Persson.

**References**

<http://persson.berkeley.edu/distmesh/>

P.-O. Persson, G. Strang, *A Simple Mesh Generator in MATLAB*. *SIAM Review*, Volume 46 (2), pp. 329-345, June 2004

**See Also**

[distmesh2d](#), [mesh.drectangle](#), [mesh.diff](#), [mesh.intersect](#), [mesh.union](#)

**Examples**

```
example(distmesh2d)
```

---

mesh.diff

*Difference, union and intersection operation on two regions*

---

**Description**

Compute the signed distances from points  $p$  to a region defined by the difference, union or intersection of regions specified by the functions `regionA` and `regionB`. `regionA` and `regionB` must accept a matrix  $p$  with 2 columns as their first argument, and must return a vector of length `nrow(p)` containing the signed distances of the supplied points in  $p$  to their respective regions.

**Usage**

```
mesh.diff(p, regionA, regionB, ...)
```

**Arguments**

<code>p</code>	A matrix with 2 columns (3 in <code>mesh.dsphere</code> ), each row representing a point in the plane.
<code>regionA</code>	vectorized function describing region A in the union / intersection / difference
<code>regionB</code>	vectorized function describing region B in the union / intersection / difference
<code>...</code>	additional arguments passed to <code>regionA</code> and <code>regionB</code>

**Value**

A vector of length `nrow(p)` containing the signed distances to the boundary of the region.

**Author(s)**

Raoul Grasman; translated from original Matlab sources of Per-Olof Persson.

**See Also**

[distmesh2d](#), [mesh.dcircle](#), [mesh.drectangle](#) [mesh.dsphere](#)

---

mesh.drectangle	<i>Rectangle distance function</i>
-----------------	------------------------------------

---

**Description**

Signed distance from points  $p$  to boundary of rectangle to allow easy definition of regions in [distmesh2d](#).

**Usage**

```
mesh.drectangle(p, x1 = -1/2, y1 = -1/2, x2 = 1/2, y2 = 1/2, ...)
```

**Arguments**

$p$	A matrix with 2 columns, each row representing a point in the plane.
$x1$	lower left corner of rectangle
$y1$	lower left corner of rectangle
$x2$	upper right corner of rectangle
$y2$	upper right corner of rectangle
...	additional arguments (not used)

**Value**

a vector of length  $nrow(p)$  containing the signed distances

**Author(s)**

Raoul Grasman; translated from original Matlab sources of Per-Olof Persson.

**References**

<http://persson.berkeley.edu/distmesh/>

*P.-O. Persson, G. Strang, A Simple Mesh Generator in MATLAB. SIAM Review, Volume 46 (2), pp. 329-345, June 2004*

**See Also**

[distmesh2d](#), [mesh.drectangle](#), [mesh.diff](#), [mesh.intersect](#), [mesh.union](#)

**Examples**

```
example(distmesh2d)
```



---

mesh.dsphere	<i>Sphere distance function</i>
--------------	---------------------------------

---

**Description**

Signed distance from points  $p$  to boundary of sphere to allow easy definition of regions in [distmeshnd](#).

**Usage**

```
mesh.dsphere(p, radius = 1, ...)
```

**Arguments**

$p$	A matrix with 2 columns (3 in <code>mesh.dsphere</code> ), each row representing a point in the plane.
radius	radius of sphere
...	additional arguments (not used)

**Value**

A vector of length `nrow(p)` containing the signed distances to the sphere

**Author(s)**

Raoul Grasman; translated from original Matlab sources of Per-Olof Persson.

**References**

<http://persson.berkeley.edu/distmesh/>

*P.-O. Persson, G. Strang, A Simple Mesh Generator in MATLAB. SIAM Review, Volume 46 (2), pp. 329-345, June 2004*

**See Also**

[distmeshnd](#)

**Examples**

```
example(distmeshnd)
```

---

mesh.hunif	<i>Uniform desired edge length</i>
------------	------------------------------------

---

**Description**

Uniform desired edge length function of position to allow easy definition of regions when passed as the fh argument of [distmesh2d](#) or [distmeshnd](#).

**Usage**

```
mesh.hunif(p, ...)
```

**Arguments**

p	A n-by-m matrix, each row representing a point in an m-dimensional space.
...	additional arguments (not used)

**Value**

Vector of ones of length n.

**Author(s)**

Raoul Grasman; translated from original Matlab sources of Per-Olof Persson.

**See Also**

[distmesh2d](#) and [distmeshnd](#).

---

pol2cart	<i>Transform polar or cylindrical coordinates to Cartesian coordinates.</i>
----------	---

---

**Description**

The inputs theta, r, (and z) must be the same shape, or scalar. If called with a single matrix argument then each row of P represents the polar/(cylindrical) coordinate (theta, r (, z)).

**Usage**

```
pol2cart(theta, r = NULL, z = NULL)
```

**Arguments**

theta	describes the angle relative to the positive x-axis.
r	is the distance to the z-axis (0, 0, z).
z	(optional) is the z-coordinate

**Value**

a matrix C where each row represents one Cartesian coordinate (x, y (, z)).

**Author(s)**

Kai Habel

David Sterratt

**See Also**

[cart2pol](#), [sph2cart](#), [cart2sph](#)

---

polyarea

*Determines area of a polygon by triangle method.*

---

**Description**

Determines area of a polygon by triangle method. The variables x and y define the vertex pairs, and must therefore have the same shape. They can be either vectors or arrays. If they are arrays then the columns of x and y are treated separately and an area returned for each.

**Usage**

```
polyarea(x, y, d = 1)
```

**Arguments**

x	X coordinates of vertices.
y	Y coordinates of vertices.
d	Dimension of array to work along.

**Details**

If the optional dim argument is given, then polyarea works along this dimension of the arrays x and y.

**Value**

Area(s) of polygon(s).

**Author(s)**

David Sterratt based on the octave sources by David M. Doolin

**Examples**

```
x <- c(1, 1, 3, 3, 1)
y <- c(1, 3, 3, 1, 1)
polyarea(x, y)
polyarea(cbind(x, x), cbind(y, y)) ## c(4, 4)
polyarea(cbind(x, x), cbind(y, y), 1) ## c(4, 4)
polyarea(rbind(x, x), rbind(y, y), 2) ## c(4, 4)
```

---

rbox

*Generate various point distributions*


---

**Description**

Default is corners of a hypercube.

**Usage**

```
rbox(n = 3000, D = 3, B = 0.5, C = NA)
```

**Arguments**

n                    number of random points in hypercube  
D                    number of dimensions of hypercube  
B                    bounding box coordinate - faces will be -B and B from origin  
C                    add a unit hypercube to the output - faces will be -C and C from origin

**Value**

Matrix of points

**Author(s)**

David Sterratt

---

sph2cart

*Transform spherical coordinates to Cartesian coordinates*


---

**Description**

The inputs theta, phi, and r must be the same shape, or scalar. If called with a single matrix argument then each row of S represents the spherical coordinate (theta, phi, r).

**Usage**

```
sph2cart(theta, phi = NULL, r = NULL)
```

**Arguments**

theta	describes the angle relative to the positive x-axis.
phi	is the angle relative to the xy-plane.
r	is the distance to the origin $(0, 0, 0)$ .

If only a single return argument is requested then return a matrix C where each row represents one Cartesian coordinate  $(x, y, z)$ .

**Author(s)**

Kai Habel  
David Sterratt

**See Also**

[cart2sph](#), [pol2cart](#), [cart2pol](#)

---

surf.tri

*Find surface triangles from tetrahedral mesh*

---

**Description**

Find surface triangles from tetrahedral mesh typically obtained with [delaunayn](#).

**Usage**

surf.tri(p, t)

**Arguments**

p	An n-by-3 matrix. The rows of p represent n points in dim-dimensional space.
t	Matrix with 4 columns, interpreted as output of <a href="#">delaunayn</a> .

**Details**

surf.tri and [convhulln](#) serve a similar purpose in 3D, but surf.tri also works for non-convex meshes obtained e.g. with [dismeshnd](#). It also does not produce currently unavoidable diagnostic output on the console as convhulln does at the Rterm console—i.e., surf.tri is silent.

**Value**

An m-by-3 index matrix of which each row defines a triangle. The indices refer to the rows in p.

**Note**

surf.tri was based on Matlab code for mesh of Per-Olof Persson (<http://persson.berkeley.edu/dismesh/>).

**Author(s)**

Raoul Grasman

**See Also**[tri.mesh](#), [convhulln](#), [surf.tri](#), [distmesh2d](#)**Examples**

```
## Not run:
# more extensive example of surf.tri

# url's of publically available data:
data1.url = "http://neuroimage.usc.edu/USCPhantom/mesh_data.bin"
data2.url = "http://neuroimage.usc.edu/USCPhantom/CT_PCS_trans.bin"

meshdata = R.matlab::readMat(url(data1.url))
elec = R.matlab::readMat(url(data2.url))$eeg.ct2pcs/1000
brain = meshdata$mesh.brain[,c(1,3,2)]
scalp = meshdata$mesh.scalp[,c(1,3,2)]
skull = meshdata$mesh.skull[,c(1,3,2)]
tbr = t(surf.tri(brain, delaunayn(brain)))
tsk = t(surf.tri(skull, delaunayn(skull)))
tsc = t(surf.tri(scalp, delaunayn(scalp)))
rgl::triangles3d(brain[tbr,1], brain[tbr,2], brain[tbr,3],col="gray")
rgl::triangles3d(skull[tsk,1], skull[tsk,2], skull[tsk,3],col="white", alpha=0.3)
rgl::triangles3d(scalp[tsc,1], scalp[tsc,2], scalp[tsc,3],col="#a53900", alpha=0.6)
rgl::view3d(-40,30,.4,zoom=.03)
lx = c(-.025,.025); ly = -c(.02,.02);
rgl::spheres3d(elec[,1],elec[,3],elec[,2],radius=.0025,col='gray')
rgl::spheres3d( lx, ly,.11,radius=.015,col="white")
rgl::spheres3d( lx, ly,.116,radius=.015*.7,col="brown")
rgl::spheres3d( lx, ly,.124,radius=.015*.25,col="black")

## End(Not run)
```

tetramesh

*Render tetrahedron mesh (3D)***Description**

tetramesh(T, X, col) uses the [rgl](#) package to display the tetrahedrons defined in the m-by-4 matrix T as mesh. Each row of T specifies a tetrahedron by giving the 4 indices of its points in X.

**Usage**

```
tetramesh(T, X, col = grDevices::heat.colors(nrow(T)), clear = TRUE, ...)
```

**Arguments**

T	T is a m-by-3 matrix in trimesh and m-by-4 in tetramesh. A row of T contains indices into X of the vertices of a triangle/tetrahedron. T is usually the output of delaunayn.
X	X is an n-by-2/n-by-3 matrix. The rows of X represent n points in 2D/3D space.
col	The tetrahedron colour. See rgl documentation for details.
clear	Should the current rendering device be cleared?
...	Parameters to the rendering device. See the <a href="#">rgl</a> package.

**Author(s)**

Raoul Grasman

**See Also**

[trimesh](#), [rgl](#), [delaunayn](#), [convhulln](#), [surf.tri](#)

**Examples**

```
## Not run:
# example delaunayn
d = c(-1,1)
pc = as.matrix(rbind(expand.grid(d,d,d),0))
tc = delaunayn(pc)

# example tetramesh
clr = rep(1,3) %0% (1:nrow(tc)+1)
rgl::view3d(60,fov=20)
rgl::light3d(270,60)
tetramesh(tc,pc,alpha=0.7,col=clr)

## End(Not run)
```

---

to.mesh3d

---

*Convert convhulln object to RGL mesh*


---

**Description**

Convert convhulln object to RGL mesh

**Usage**

```
to.mesh3d(x, ...)
```

**Arguments**

x	<a href="#">convhulln</a> object
...	Arguments to <a href="#">qmesh3d</a> or <a href="#">tmesh3d</a>

**Value**

[mesh3d](#) object, which can be displayed in RGL with [dot3d](#), [wire3d](#) or [shade3d](#)

**See Also**

[as.mesh3d](#)

---

trimesh

*Display triangles mesh (2D)*


---

**Description**

`trimesh(T, p)` displays the triangles defined in the  $m$ -by-3 matrix  $T$  and points  $p$  as a mesh. Each row of  $T$  specifies a triangle by giving the 3 indices of its points in  $X$ .

**Usage**

```
trimesh(T, p, p2, add = FALSE, axis = FALSE, boxed = FALSE, ...)
```

**Arguments**

<code>T</code>	$T$ is a $m$ -by-3 matrix. A row of $T$ contains indices into $X$ of the vertices of a triangle. $T$ is usually the output of <a href="#">delaunayn</a> .
<code>p</code>	A vector or a matrix.
<code>p2</code>	if $p$ is not a matrix $p$ and $p2$ are bind to a matrix with <code>cbind</code> .
<code>add</code>	Add to existing plot in current active device?
<code>axis</code>	Draw axes?
<code>boxed</code>	Plot box?
<code>...</code>	Parameters to the rendering device. See the <a href="#">rgl</a> package.

**Author(s)**

Raoul Grasman

**See Also**

[tetramesh](#), [rgl](#), [delaunayn](#), [convhulln](#), [surf.tri](#)

**Examples**

```
#example trimesh
p = cbind(x=rnorm(30), y=rnorm(30))
tt = delaunayn(p)
trimesh(tt,p)
```



---

tsearch *Search for the enclosing Delaunay convex hull*

---

### Description

For `t <- delaunay(cbind(x, y))`, where `(x, y)` is a 2D set of points, `tsearch(x, y, t, xi, yi)` finds the index in `t` containing the points `(xi, yi)`. For points outside the convex hull the index is NA.

### Usage

```
tsearch(x, y, t, xi, yi, bary = FALSE, method = "quadtree")
```

### Arguments

<code>x</code>	X-coordinates of triangulation points
<code>y</code>	Y-coordinates of triangulation points
<code>t</code>	Triangulation, e.g. produced by <code>t &lt;- delaunayn(cbind(x, y))</code>
<code>xi</code>	X-coordinates of points to test
<code>yi</code>	Y-coordinates of points to test
<code>bary</code>	If TRUE return barycentric coordinates as well as index of triangle.
<code>method</code>	One of "quadtree" or "orig". The Quadtree algorithm is much faster and new from version 0.4.0. The orig option uses the tsearch algorithm adapted from Octave code. Its use is deprecated and it may be removed from a future version of the package.

### Value

If `bary` is FALSE, the index in `t` containing the points `(xi, yi)`. For points outside the convex hull the index is NA. If `bary` is TRUE, a list containing:

**list("idx")** the index in `t` containing the points `(xi, yi)`

**list("p")** a 3-column matrix containing the barycentric coordinates with respect to the enclosing triangle of each point `(xi, yi)`.

### Note

The original Octave function is Copyright (C) 2007-2012 David Bateman

### Author(s)

Jean-Romain Roussel (Quadtree algorithm), David Sterratt (Octave-based implementation)

### See Also

[tsearchn](#), [delaunayn](#)

---

tsearchn

*Search for the enclosing Delaunay convex hull*


---

### Description

For  $t = \text{delaunayn}(x)$ , where  $x$  is a set of points in  $N$  dimensions,  $\text{tsearchn}(x, t, xi)$  finds the index in  $t$  containing the points  $xi$ . For points outside the convex hull,  $idx$  is NA.  $\text{tsearchn}$  also returns the barycentric coordinates  $p$  of the enclosing triangles.

### Usage

```
tsearchn(x, t, xi, ...)
```

### Arguments

$x$	An $N$ -column matrix, in which each row represents a point in $N$ -dimensional space.
$t$	A matrix with $N + 1$ columns. A row of $t$ contains indices into $x$ of the vertices of an $N$ -dimensional simplex. $t$ is usually the output of <code>delaunayn</code> .
$xi$	An $M$ -by- $N$ matrix. The rows of $xi$ represent $M$ points in $N$ -dimensional space whose positions in the mesh are being sought.
$\dots$	Additional arguments

### Details

If  $x$  is NA and the  $t$  is a `delaunayn` object produced by `delaunayn` with the `full` option, then use the `Qhull` library to perform the search. Please note that this is experimental in geometry version 0.4.0 and is only partly tested for 3D hulls, and does not yet work for hulls of 4 dimensions and above.

### Value

A list containing:

$idx$  An  $M$ -long vector containing the indices of the row of  $t$  in which each point in  $xi$  is found.

$p$  An  $M$ -by- $N + 1$  matrix containing the barycentric coordinates with respect to the enclosing simplex of each point in  $xi$ .

### Note

Based on the Octave function Copyright (C) 2007-2012 David Bateman.

### Author(s)

David Sterratt

**See Also**[tsearch](#), [deleunayn](#)

---

**Unique***Extract Unique Rows*

---

**Description**

'Unique' returns a vector, data frame or array like 'x' but with duplicate elements removed.

**Usage**

```
Unique(X, rows.are.sets = FALSE)
```

**Arguments**

X	Numerical matrix.
rows.are.sets	If 'TRUE', rows are treated as sets - i.e., to define uniqueness, the order of the rows does not matter.

**Value**

Matrix of the same number of columns as x, with the unique rows in x sorted according to the columns of x. If rows.are.sets = TRUE the rows are also sorted.

**Note**

'Unique' is (under circumstances) much quicker than the more generic base function 'unique'.

**Author(s)**

Raoul Grasman

**Examples**

```
# `Unique` is faster than `unique`
x = matrix(sample(1:(4*8),4*8),ncol=4)
y = x[sample(1:nrow(x),3000,TRUE), ]
gc(); system.time(unique(y))
gc(); system.time(Unique(y))

#
z = Unique(y)
x[matorder(x),]
z[matorder(z),]
```

# Index

- \* **arith**
  - dot, 15
  - entry.value, 16
  - extprod3d, 17
  - matmax, 21
  - mesh.dcircle, 22
  - mesh.drectangle, 24
  - mesh.dsphere, 25
  - Unique, 35
- \* **array**
  - dot, 15
  - entry.value, 16
  - extprod3d, 17
  - matmax, 21
  - Unique, 35
- \* **dplot**
  - convhulln, 7
  - delaunayn, 9
  - distmesh2d, 11
  - distmeshnd, 13
  - surf.tri, 29
- \* **graphs**
  - convhulln, 7
  - delaunayn, 9
  - distmesh2d, 11
  - distmeshnd, 13
- \* **hplot**
  - tetramesh, 30
  - trimesh, 32
- \* **math**
  - convhulln, 7
  - delaunayn, 9
  - distmesh2d, 11
  - distmeshnd, 13
  - dot, 15
  - entry.value, 16
  - extprod3d, 17
  - mesh.dcircle, 22
  - mesh.drectangle, 24
  - mesh.dsphere, 25
  - surf.tri, 29
  - Unique, 35
- \* **optimize**
  - distmesh2d, 11
  - distmeshnd, 13
  - surf.tri, 29
- as.mesh3d, 32
- bary2cart, 3, 5
- cart2bary, 3, 4
- cart2pol, 5, 6, 27, 29
- cart2sph, 6, 6, 27, 29
- convex.hull, 8
- convhulln, 7, 10, 18, 19, 21, 29–32
- delaunayn, 8, 9, 12–15, 29, 31–35
- distmesh2d, 10, 11, 14, 15, 22–24, 26, 30
- distmeshnd, 13, 25, 26, 29
- dot, 15
- dot3d, 32
- drop, 17
- entry.value, 16
- entry.value<- (entry.value), 16
- extprod3d, 17
- feasible.point, 17, 21
- halfspacen, 18, 20, 21
- inhulln, 19, 21
- intersectn, 8, 20
- matmax, 21
- matmin (matmax), 21
- matorder (matmax), 21
- matsort (matmax), 21
- mesh.dcircle, 11, 13, 22, 24

mesh.diff, [11](#), [13](#), [15](#), [23](#), [23](#), [24](#)  
mesh.drectangle, [13](#), [23](#), [24](#), [24](#)  
mesh.dsphere, [14](#), [15](#), [24](#), [25](#)  
mesh.hunif, [11](#), [14](#), [15](#), [26](#)  
mesh.intersect, [13](#), [15](#), [23](#), [24](#)  
mesh.intersect (mesh.diff), [23](#)  
mesh.union, [13](#), [15](#), [23](#), [24](#)  
mesh.union (mesh.diff), [23](#)  
mesh3d, [32](#)

pol2cart, [6](#), [26](#), [29](#)  
polyarea, [27](#)

qmesh3d, [31](#)

rbox, [28](#)  
rgl, [30–32](#)

shade3d, [32](#)  
sph2cart, [6](#), [27](#), [28](#)  
surf.tri, [8](#), [10](#), [29](#), [30–32](#)

tetramesh, [30](#), [32](#)  
tmesh3d, [31](#)  
to.mesh3d, [31](#)  
tri.mesh, [10](#), [13](#), [15](#), [30](#)  
trimesh, [31](#), [32](#)  
tsearch, [33](#), [35](#)  
tsearchn, [33](#), [34](#)

Unique, [35](#)

wire3d, [32](#)