Good-visibility maps visualization

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Given a set $V$ of viewpoints and a set $S$ of obstacles in an environmental space, the good-visibility depth of a point $q$ in relation to $V$ and $S$ is a measure of how deep or central $q$ is with respect to the points in $V$ that see $q$ while minding the obstacles of $S$. The good-visibility map determined by $V$ and $S$ is the subdivision of the environmental space in good-visibility regions where all points have the same fixed good-visibility depth. In this paper we present algorithms for computing and efficiently visualizing, using graphics hardware capabilities, good-visibility maps in the plane as well as on triangulated terrains, where the obstacles are the terrain faces. Finally, we present experimental results obtained with the implementation of our algorithms.

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