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.