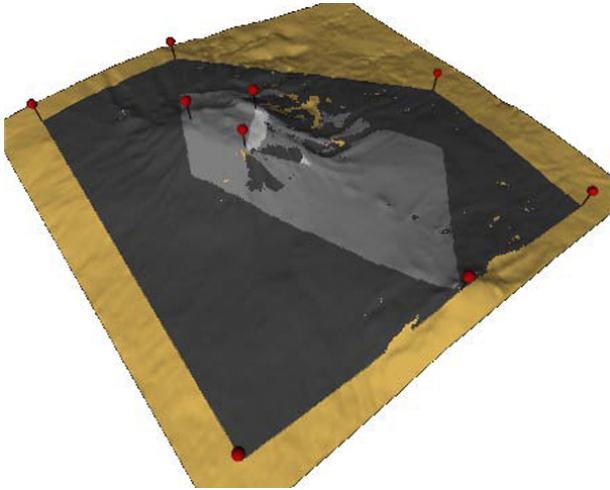


# Good-visibility maps visualization

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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.