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Good-visibility maps visualization

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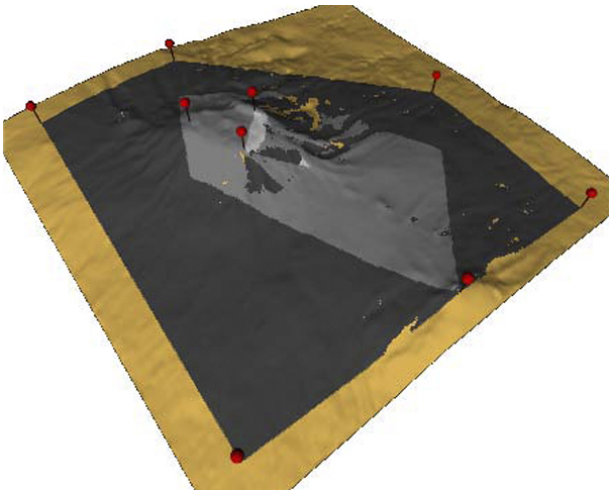

Given a set V of viewpoints and a set S of obstacles in an environmental space, the good-visibility depth of a point q in relation to V and S is a measure of how deep or central q is with respect to the points in V that see q while minding the obstacles of S. The good-visibility map determined by V and 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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