Computational Geometry Lecture

Applications of WSPD & Visibility Graphs

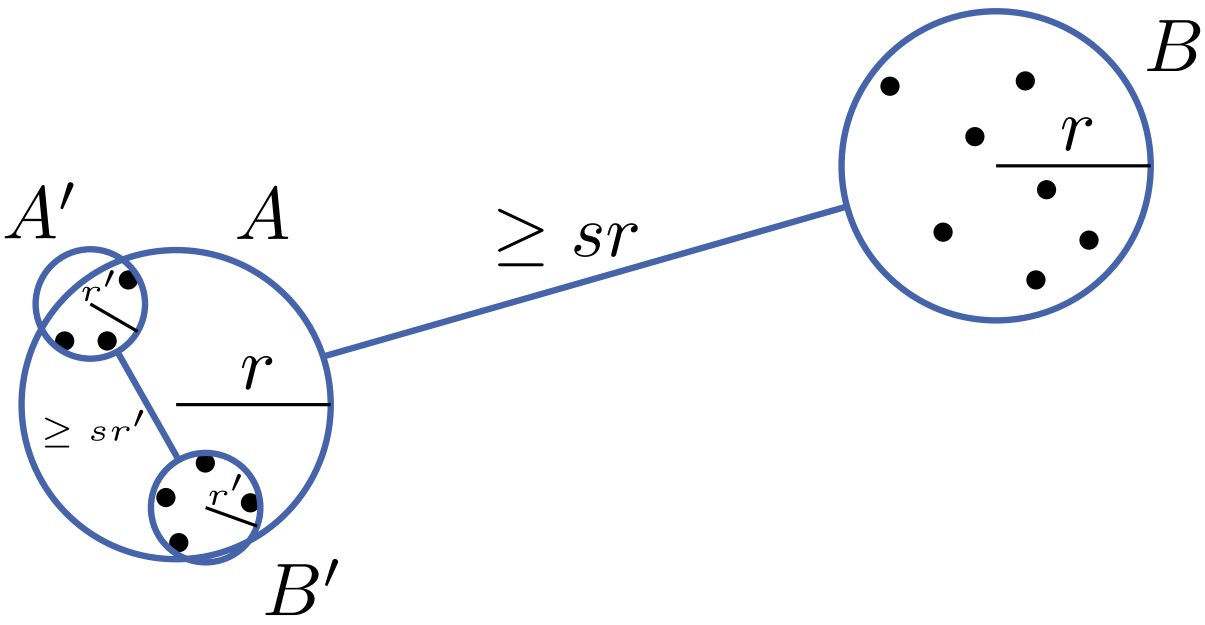
INSTITUT FÜR THEORETISCHE INFORMATIK · FAKULTÄT FÜR INFORMATIK

Tamara Mchedlidze · Darren Strash

25.01.2016

Recall: Well-Separated Pair Decomposition

Def: A pair of disjoint point sets A and B in $\mathbb{R}^d$ is called s-**well separated** for some $s > 0$, if A and B can each be covered by a ball of radius r whose distance is at least sr.



Recall: Well-Separated Pair Decomposition

Def: A pair of disjoint point sets A and B in $\mathbb{R}^d$ is called s-**well separated** for some $s > 0$, if A and B can each be covered by a ball of radius r whose distance is at least sr.

Def: For a point set P and some $s > 0$ an s-**well separated pair decomposition** (s-WSPD) is a set of pairs $\{\{A_1, B_1\}, \ldots, \{A_m, B_m\}\}$ with

- $A_i, B_i \subset P$ for all i
- $A_i \cap B_i = \emptyset$ for all i
- $\bigcup_{i=1}^{m} A_i \otimes B_i = P \otimes P$
- $\{A_i, B_i\}$ s-well separated for all i

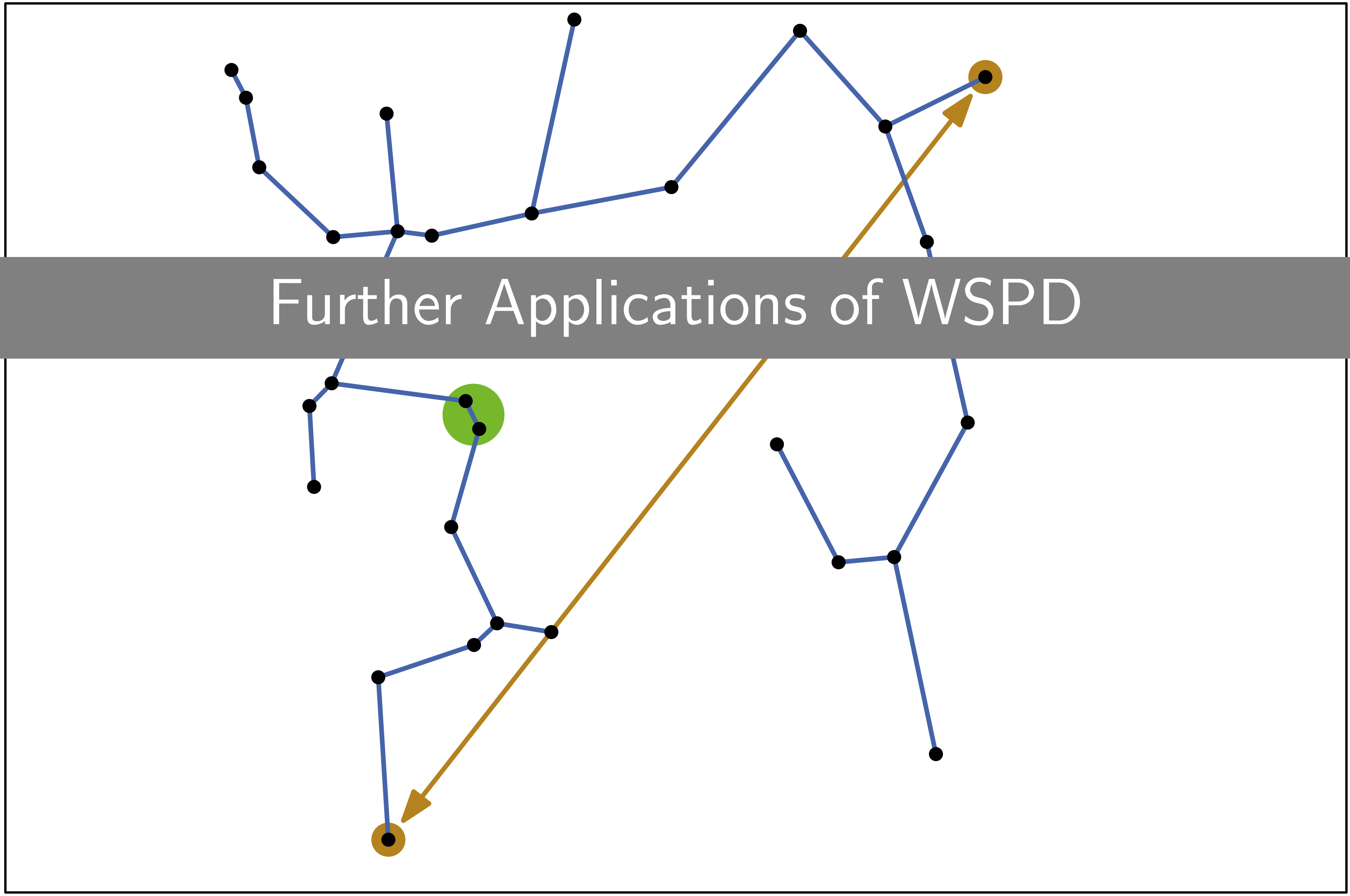
Recall: Well-Separated Pair Decomposition

Def: A pair of disjoint point sets A and B in $\mathbb{R}^d$ is called s-**well separated** for some $s > 0$, if A and B can each be covered by a ball of radius r whose distance is at least sr.

Def: For a point set P and some $s > 0$ an s-**well separated pair decomposition** (s-WSPD) is a set of pairs $\{\{A_1, B_1\}, \ldots, \{A_m, B_m\}\}$ with

- $A_i, B_i \subset P$ for all i
- $A_i \cap B_i = \emptyset$ for all i
- $\bigcup_{i=1}^{m} A_i \otimes B_i = P \otimes P$
- $\{A_i, B_i\}$ s-well separated for all i

Thm 3: Given a point set P in $\mathbb{R}^d$ and $s \geq 1$ we can construct an s-WSPD with $O(s^d n)$ pairs in time $O(n \log n + s^d n)$.



Further Applications of WSPD

Euclidean MST

Problem: Given a point set P find a minimum spanning tree (MST) in the Euclidean graph $\mathcal{EG}(P)$.

Euclidean MST

Problem: Given a point set P find a minimum spanning tree (MST) in the Euclidean graph $\mathcal{EG}(P)$.

Prim: MST in a graph $G = (V, E)$ can be computed in $O(|E| + |V| \log |V|)$ time.

Euclidean MST

Karlsruhe Institute of Technology

Problem: Given a point set P find a minimum spanning tree (MST) in the Euclidean graph $\mathcal{EG}(P)$.

Prim: MST in a graph $G = (V, E)$ can be computed in $O(|E| + |V| \log |V|)$ time.

- $\mathcal{EG}(P)$ has $\Theta(n^2)$ edges $\Rightarrow$ running time $O(n^2)$:-(
- $(1+\varepsilon)$-spanner for P has $O(n/\varepsilon^d)$ edges $\Rightarrow$ running time $O(n \log n + n/\varepsilon^d)$:-)

Euclidean MST

Problem: Given a point set P find a minimum spanning tree (MST) in the Euclidean graph $\mathcal{EG}(P)$.

Prim: MST in a graph $G = (V, E)$ can be computed in $O(|E| + |V| \log |V|)$ time.

- $\mathcal{EG}(P)$ has $\Theta(n^2)$ edges $\Rightarrow$ running time $O(n^2)$:-(
- $(1+\varepsilon)$-spanner for P has $O(n/\varepsilon^d)$ edges
  $\Rightarrow$ running time $O(n \log n + n/\varepsilon^d)$:-)

How good is the MST of a $(1+\varepsilon)$-spanner?

Euclidean MST

Problem: Given a point set P find a minimum spanning tree (MST) in the Euclidean graph $\mathcal{EG}(P)$.

Prim: MST in a graph $G = (V, E)$ can be computed in $O(|E| + |V| \log |V|)$ time.

- $\mathcal{EG}(P)$ has $\Theta(n^2)$ edges $\Rightarrow$ running time $O(n^2)$:-(
- $(1+\varepsilon)$-spanner for P has $O(n/\varepsilon^d)$ edges $\Rightarrow$ running time $O(n \log n + n/\varepsilon^d)$:-)

How good is the MST of a $(1+\varepsilon)$-spanner?

Thm 5: The MST obtained from a $(1+\varepsilon)$-spanner of P is a $(1+\varepsilon)$-approximation of the EMST of P.

Diameter of P

Problem: Find the diameter of a point set P (i.e., the pair $\{x, y\} \subset P$ with maximum distance).

Diameter of P

Problem: Find the diameter of a point set P (i.e., the pair $\{x, y\} \subset P$ with maximum distance).

- brute-force testing all point pairs $\Rightarrow$ running time $O(n^2)$:-(
- test distances $||\text{rep}(u)\ \text{rep}(v)||$ of all ws-pairs $\{P_u, P_v\}$ $\Rightarrow$ running time $O(n \log n + s^d n)$:-)

Diameter of P

Problem: Find the diameter of a point set P (i.e., the pair $\{x, y\} \subset P$ with maximum distance).

- brute-force testing all point pairs $\Rightarrow$ running time $O(n^2)$:-(
- test distances $||\text{rep}(u)\ \text{rep}(v)||$ of all ws-pairs $\{P_u, P_v\}$ $\Rightarrow$ running time $O(n \log n + s^d n)$:-)

How good is the computed diameter?

Diameter of P

Problem: Find the diameter of a point set P (i.e., the pair $\{x, y\} \subset P$ with maximum distance).

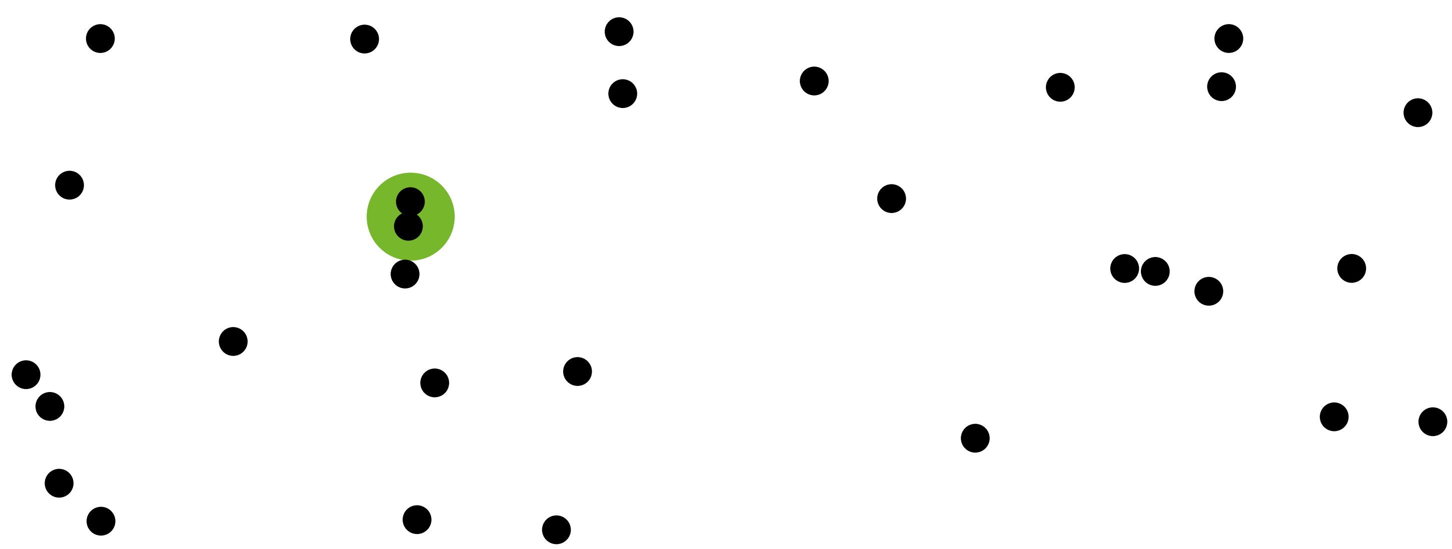
- brute-force testing all point pairs $\Rightarrow$ running time $O(n^2)$:-(
- test distances $||\text{rep}(u)\ \text{rep}(v)||$ of all ws-pairs $\{P_u, P_v\}$ $\Rightarrow$ running time $O(n \log n + s^d n)$:-)

How good is the computed diameter?

Thm 6: The diameter obtained from an s-WSPD of P for $s = 4/\varepsilon$ is a $(1 + \varepsilon)$-approximation of the diameter of P.

Closest Pair of Points

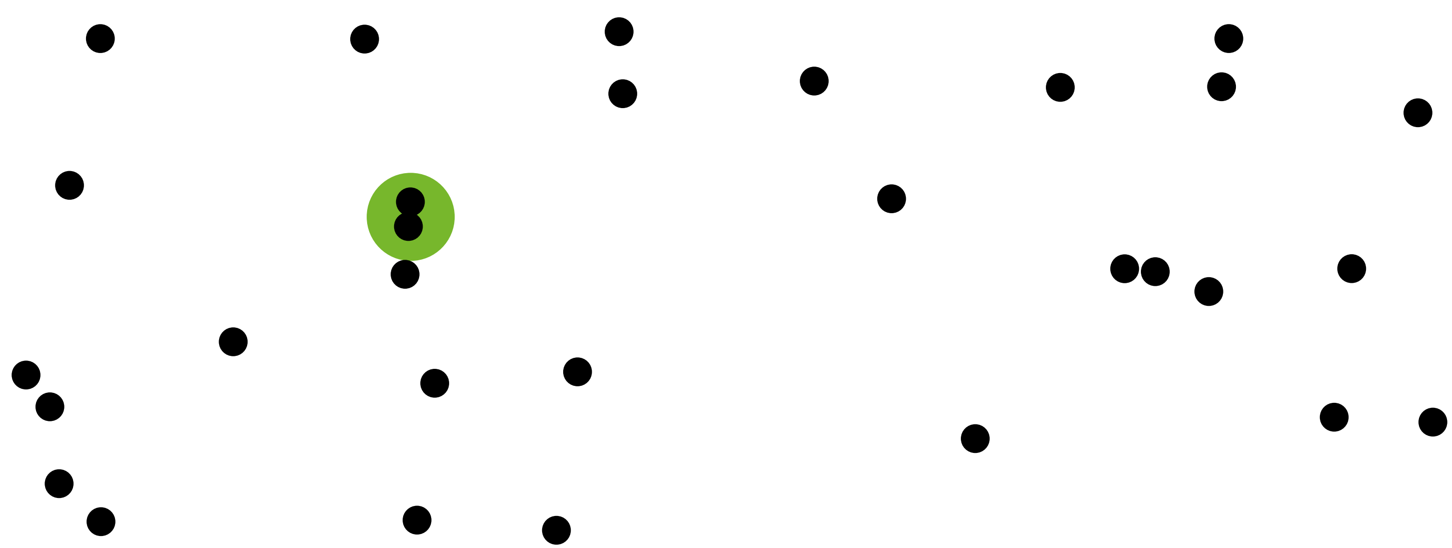
Problem: Find the pair $\{x, y\} \subset P$ with minimum distance.



Closest Pair of Points

Problem: Find the pair $\{x, y\} \subset P$ with minimum distance.

- brute-force testing all point pairs $\Rightarrow$ running time $O(n^2)$:-(
- test distances $||\text{rep}(u)\ \text{rep}(v)||$ of all ws-pairs $\{P_u, P_v\}$
  $\Rightarrow$ running time $O(n \log n + s^d n)$:-)

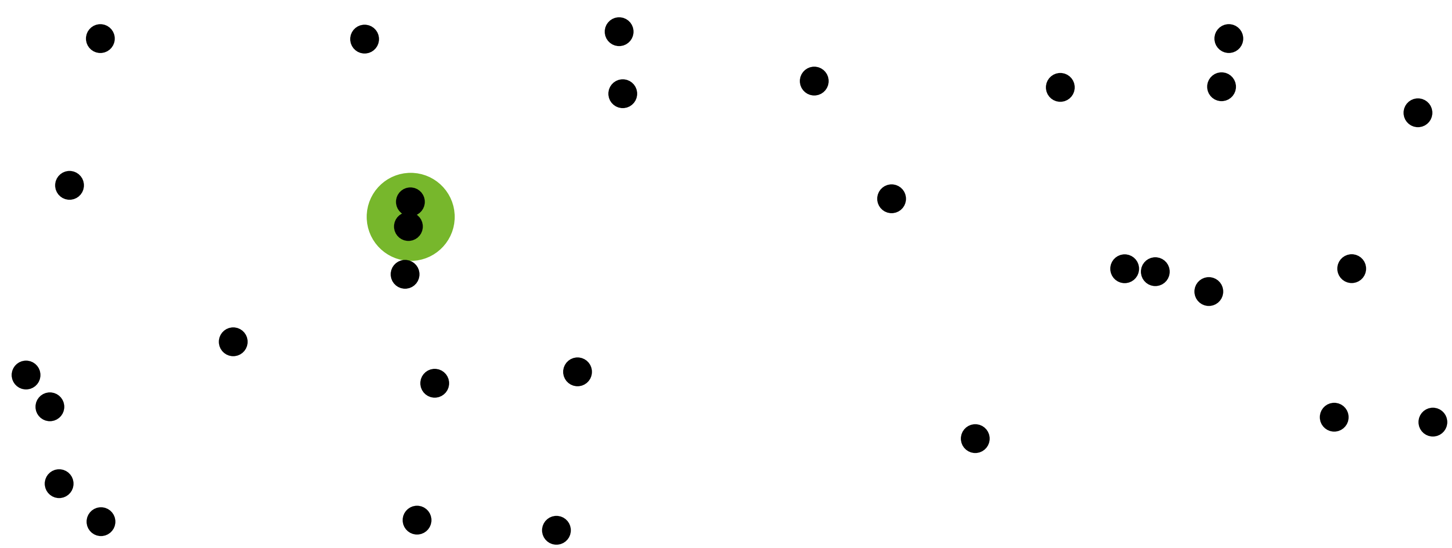


Closest Pair of Points

Problem: Find the pair $\{x, y\} \subset P$ with minimum distance.

- brute-force testing all point pairs $\Rightarrow$ running time $O(n^2)$:-(
- test distances $||\text{rep}(u)\ \text{rep}(v)||$ of all ws-pairs $\{P_u, P_v\}$ $\Rightarrow$ running time $O(n \log n + s^d n)$:-)

Exercise: For $s > 2$ this actually yields the closest pair.



Discussion

What are further applications of the WSPD?

Discussion

What are further applications of the WSPD?

WSPD is useful whenever one can do without knowing all $\Theta(n^2)$ exact distances in a point set and approximate them instead. One example are force-based layout algorithms in graph drawing, where pairwise repulsive forces of n points need to be calculated.

Discussion

What are further applications of the WSPD?

WSPD is useful whenever one can do without knowing all $\Theta(n^2)$ exact distances in a point set and approximate them instead. One example are force-based layout algorithms in graph drawing, where pairwise repulsive forces of n points need to be calculated.

Why approximate geometrically?

Discussion

Karlsruhe Institute of Technology

What are further applications of the WSPD?

WSPD is useful whenever one can do without knowing all $\Theta(n^2)$ exact distances in a point set and approximate them instead. One example are force-based layout algorithms in graph drawing, where pairwise repulsive forces of n points need to be calculated.

Why approximate geometrically?

On the one hand, this replaces slow computations by faster (but less precise) ones; on the other hand, often the input data are imprecise so that approximate solutions can be sufficient depending on the application.

Discussion

What are further applications of the WSPD?

WSPD is useful whenever one can do without knowing all $\Theta(n^2)$ exact distances in a point set and approximate them instead. One example are force-based layout algorithms in graph drawing, where pairwise repulsive forces of n points need to be calculated.

Why approximate geometrically?

On the one hand, this replaces slow computations by faster (but less precise) ones; on the other hand, often the input data are imprecise so that approximate solutions can be sufficient depending on the application.

Can we achieve the same time bounds with exact computations?

Discussion

What are further applications of the WSPD?

WSPD is useful whenever one can do without knowing all $\Theta(n^2)$ exact distances in a point set and approximate them instead. One example are force-based layout algorithms in graph drawing, where pairwise repulsive forces of n points need to be calculated.

Why approximate geometrically?

On the one hand, this replaces slow computations by faster (but less precise) ones; on the other hand, often the input data are imprecise so that approximate solutions can be sufficient depending on the application.

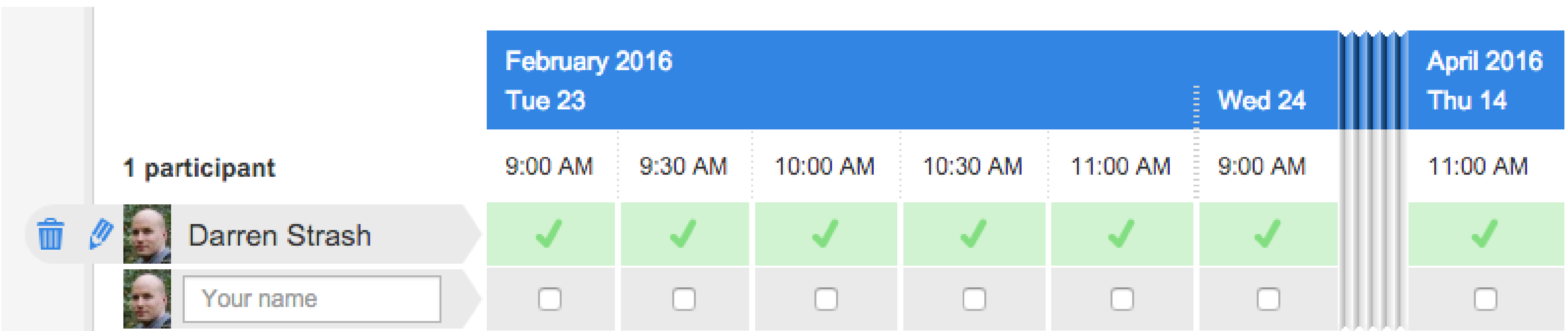
Can we achieve the same time bounds with exact computations?

In $\mathbb{R}^2$ this is often true, but not in $\mathbb{R}^d$ for $d > 2$. (e.g. EMST, diameter)

Organizational Information

Oral Exams:

Length: 30 minutes
Dates: Feb. 23, 24, 25; April 12, 13, 14
Times: 9, 9:30, 10, 10:30, 11
Doodle: Select all time slots that you have available!



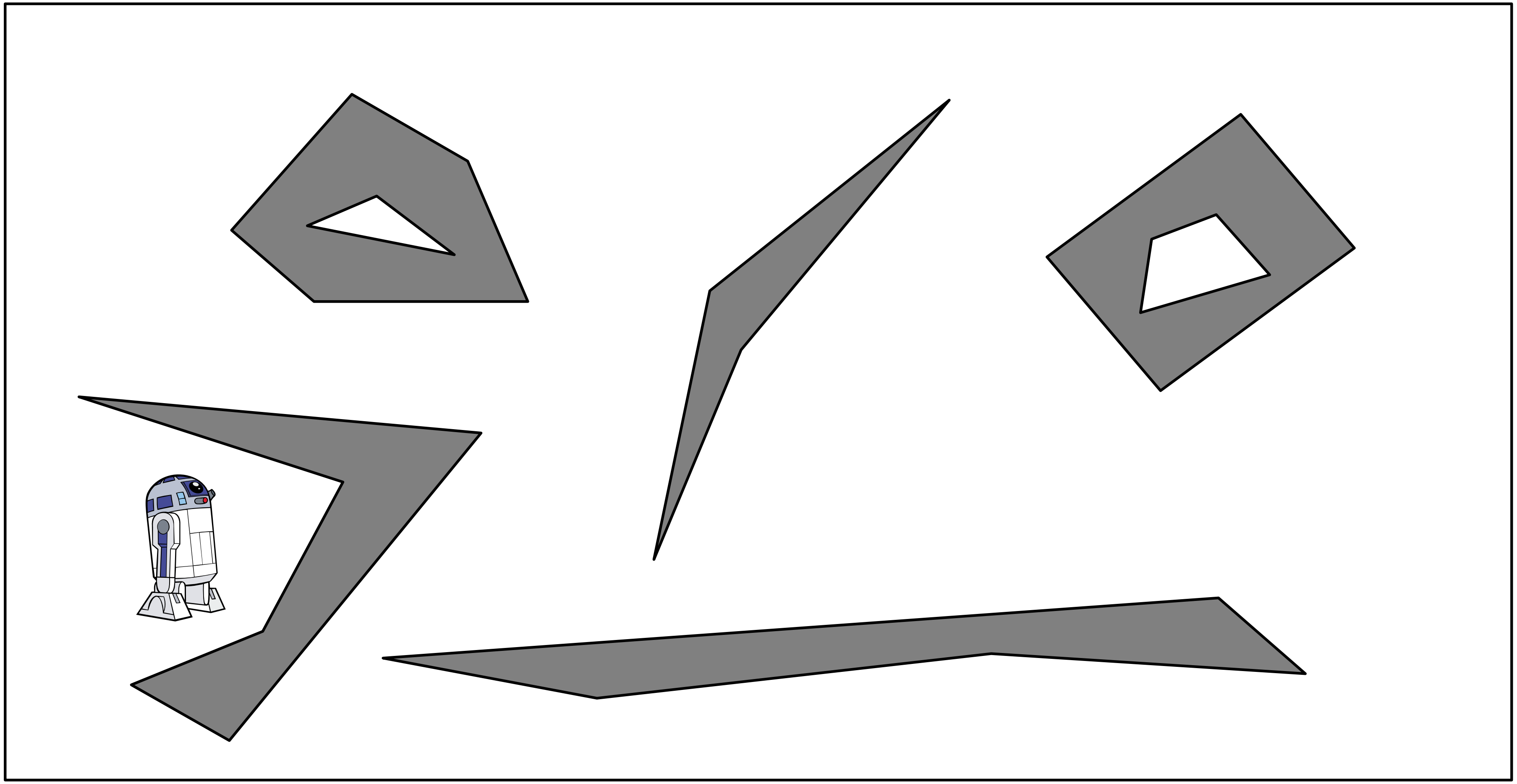
Please come to our offices and ask questions!

Project presentations:

Next week on Feb. 1 and 3.

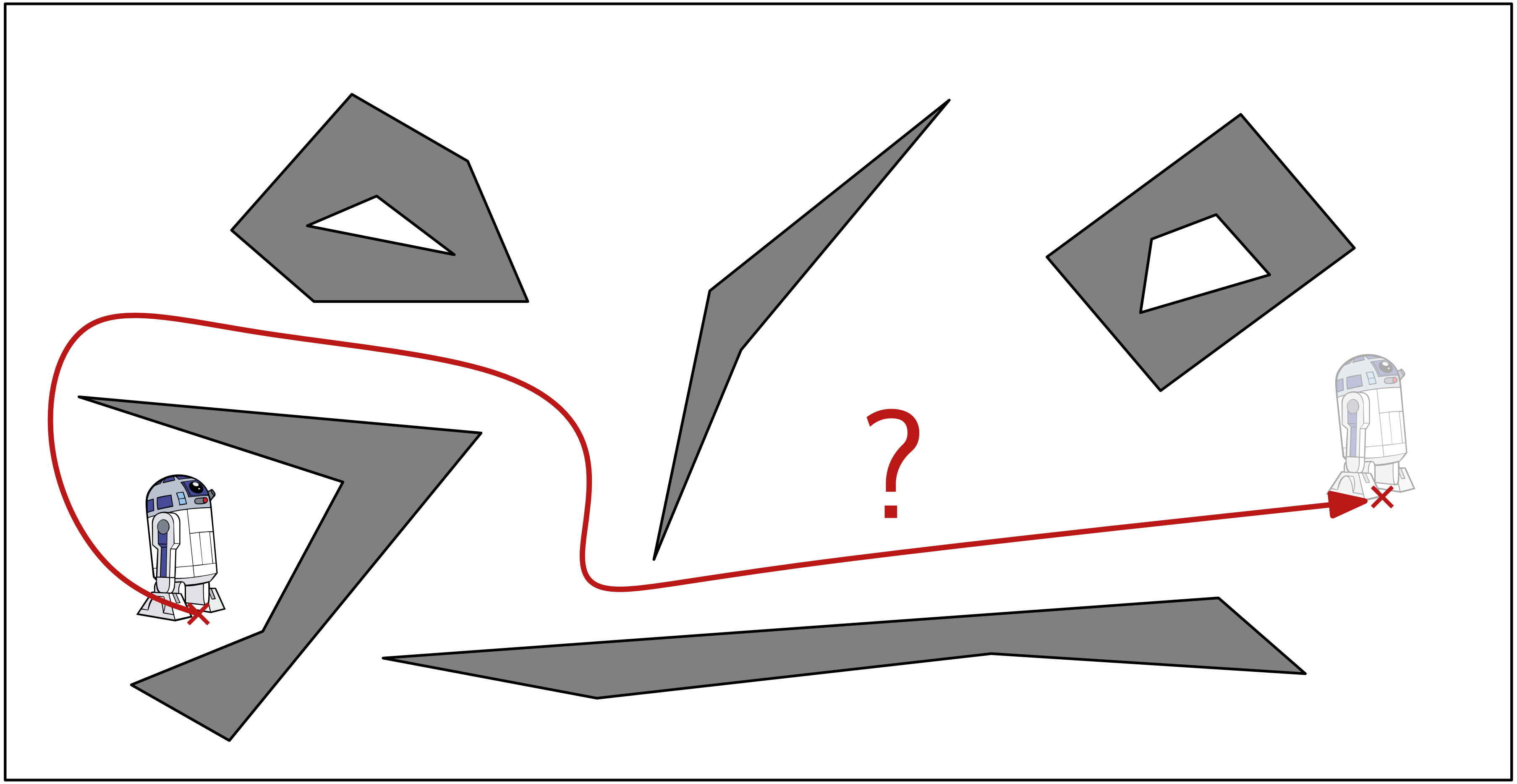
Motion planning and Visibility Graphs

Robot Motion Planning



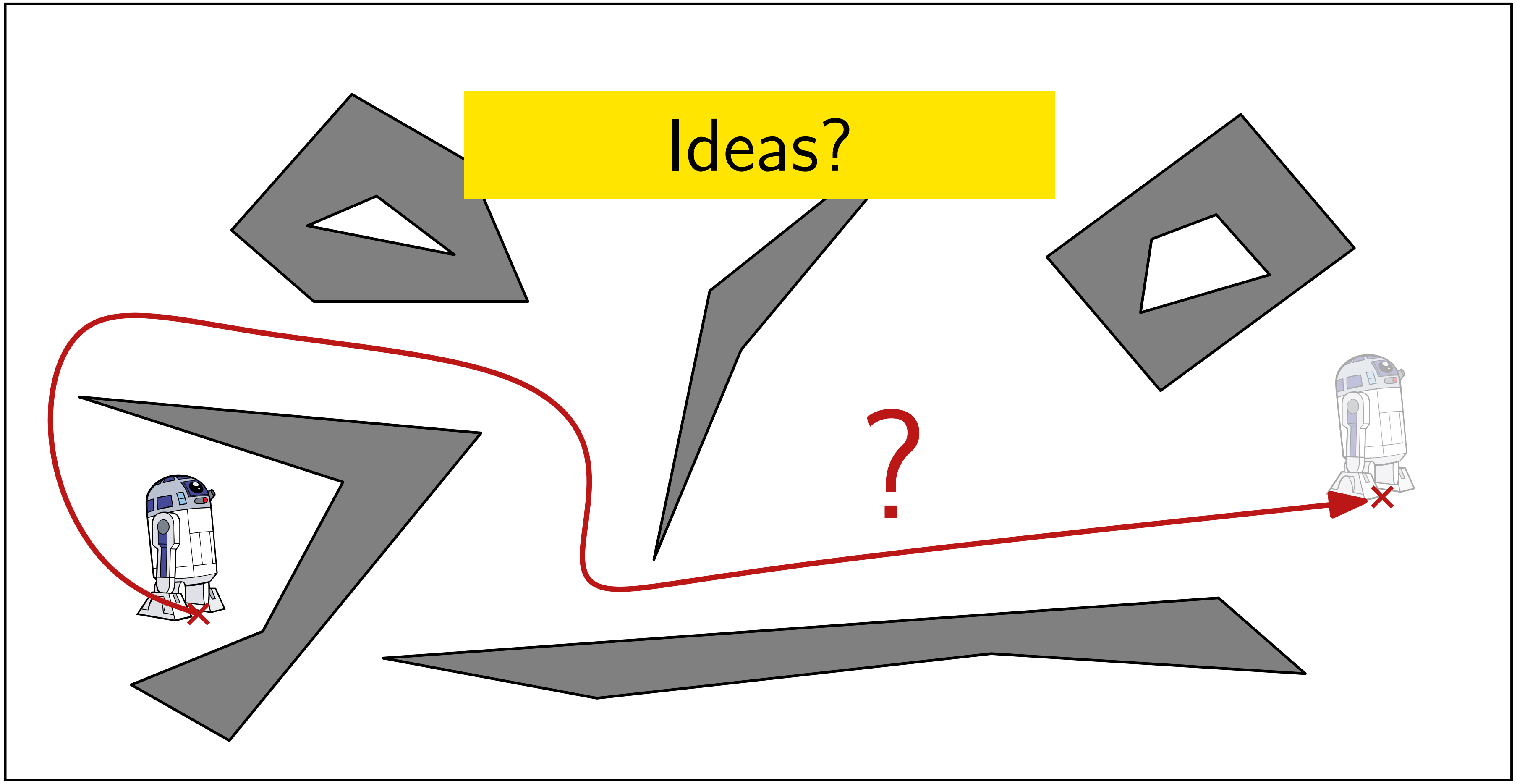
Problem: Given a (point) robot at position p_{start} in a area with polygonal obstacles, find a shortest path to p_{goal} avoiding obstacles.

Robot Motion Planning



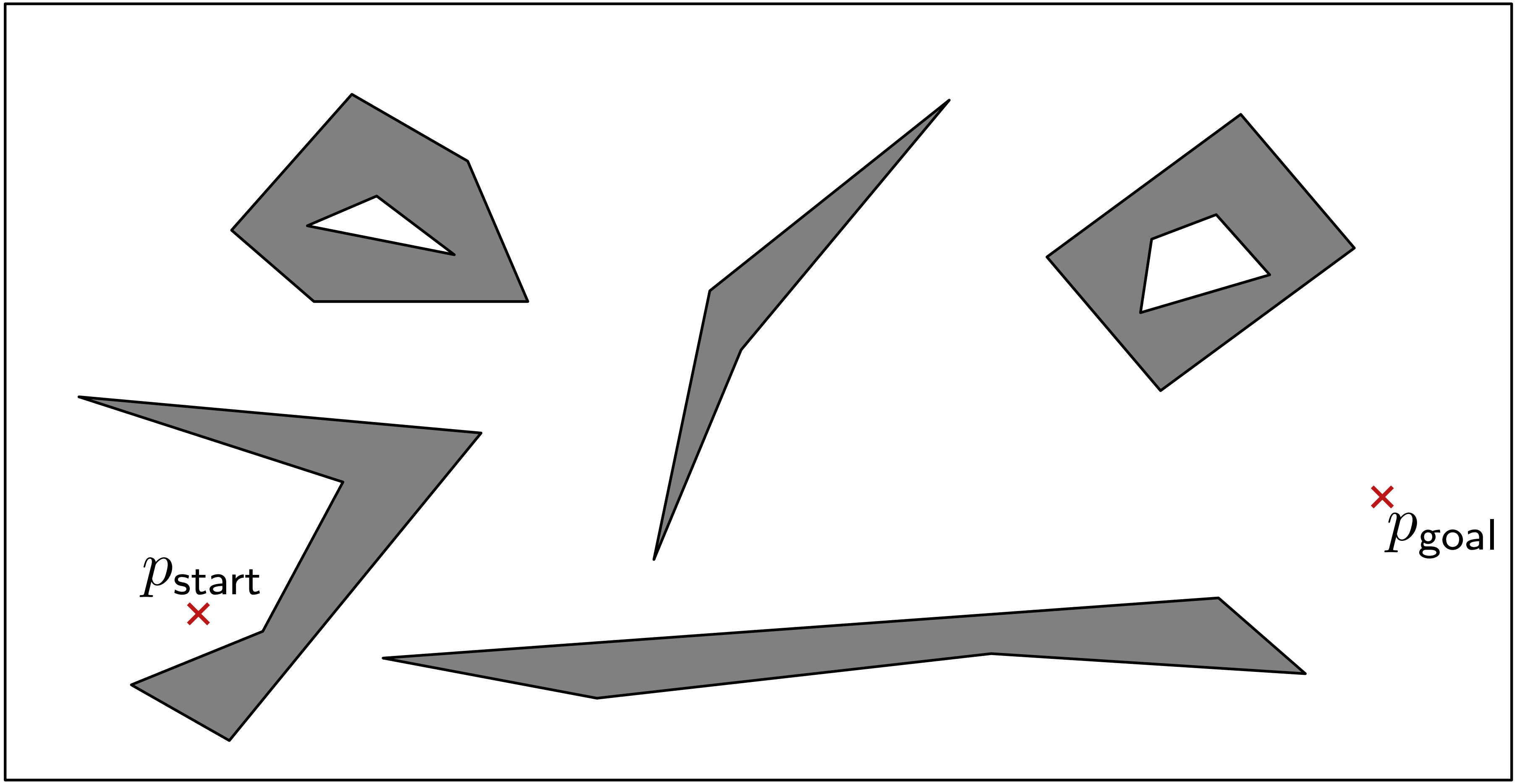
Problem: Given a (point) robot at position p_{start} in a area with polygonal obstacles, find a shortest path to p_{goal} avoiding obstacles.

Robot Motion Planning

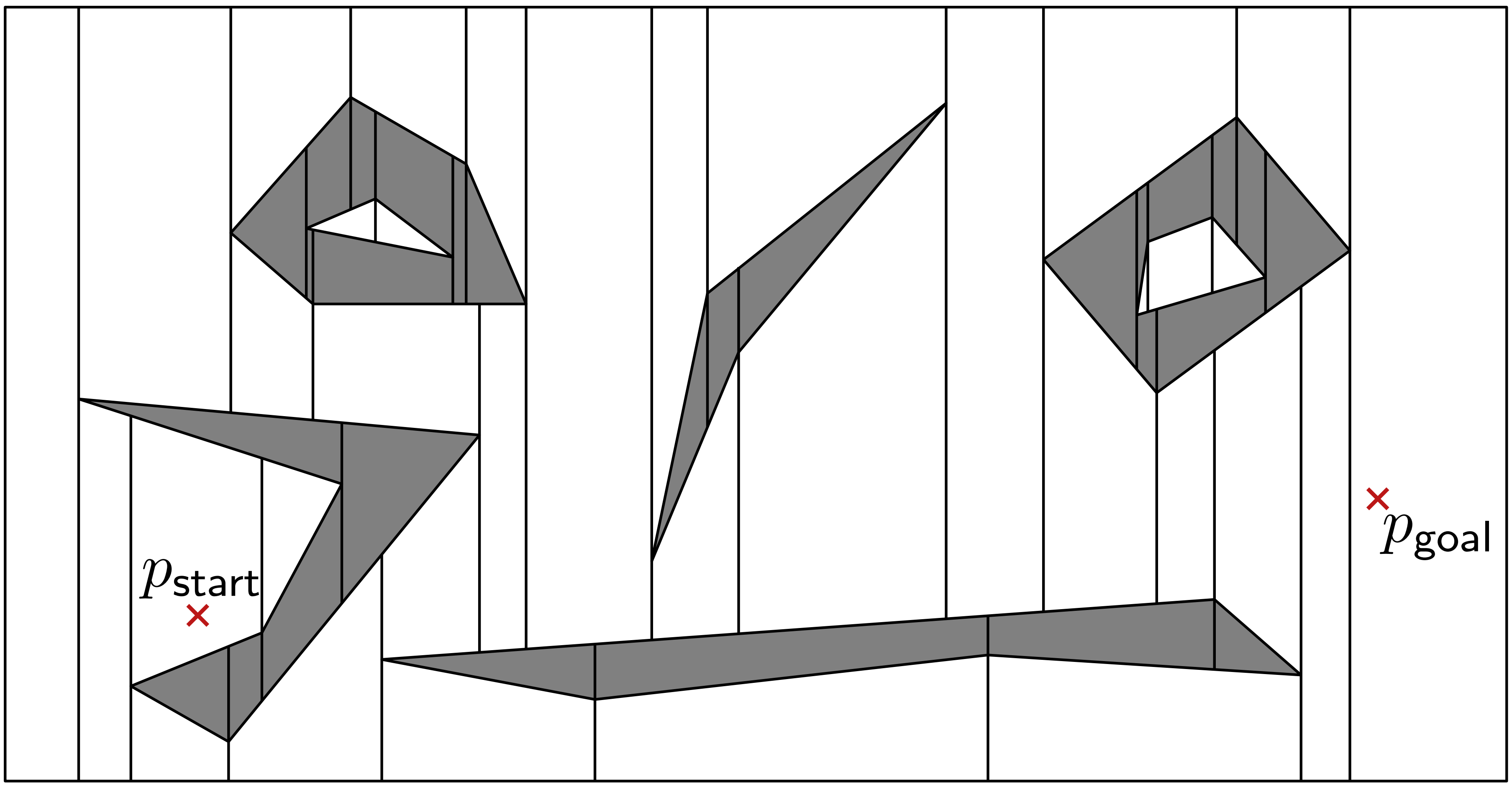


Problem: Given a (point) robot at position p_{start} in a area with polygonal obstacles, find a shortest path to p_{goal} avoiding obstacles.

First Idea: Shortest Paths in Graphs

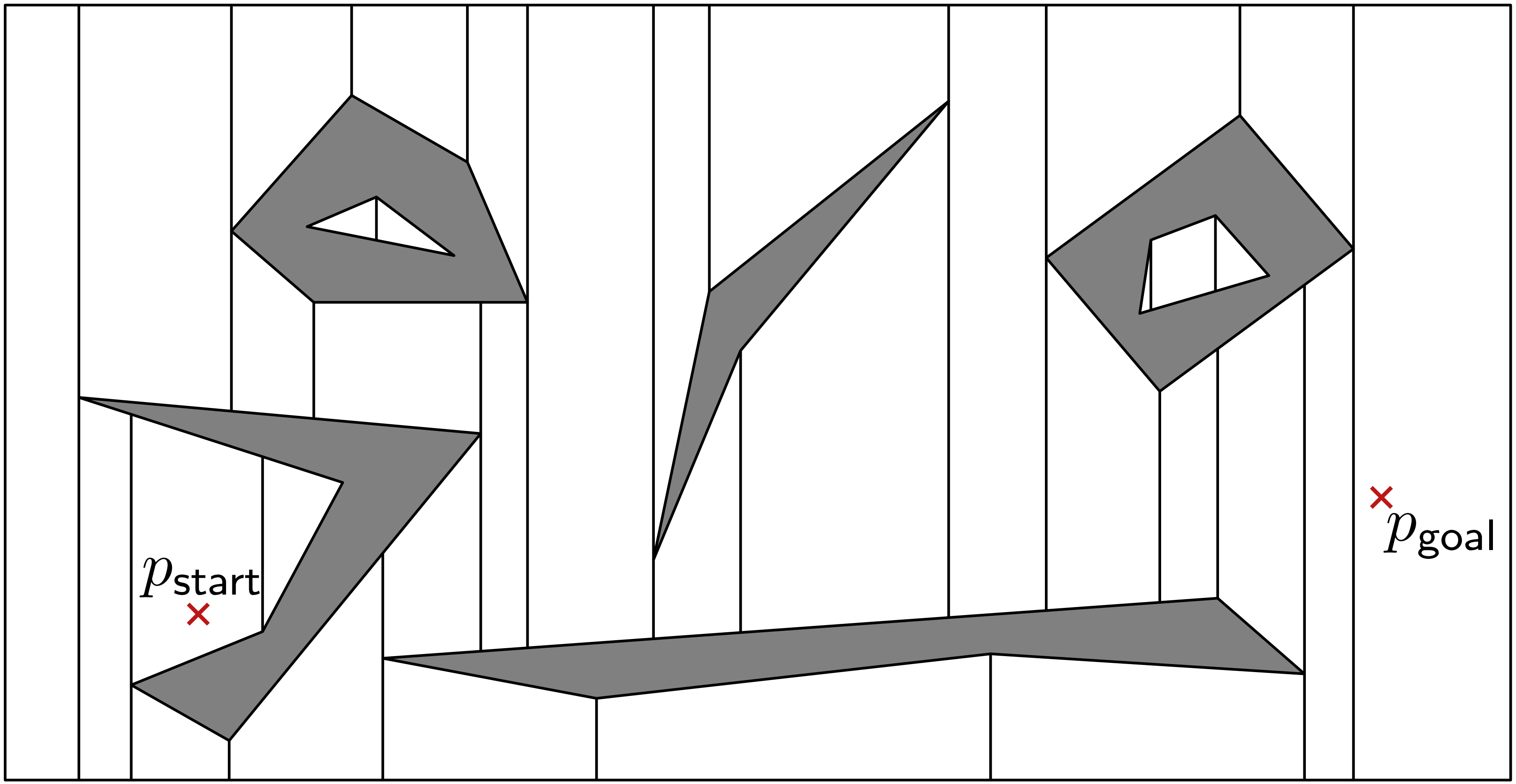


First Idea: Shortest Paths in Graphs



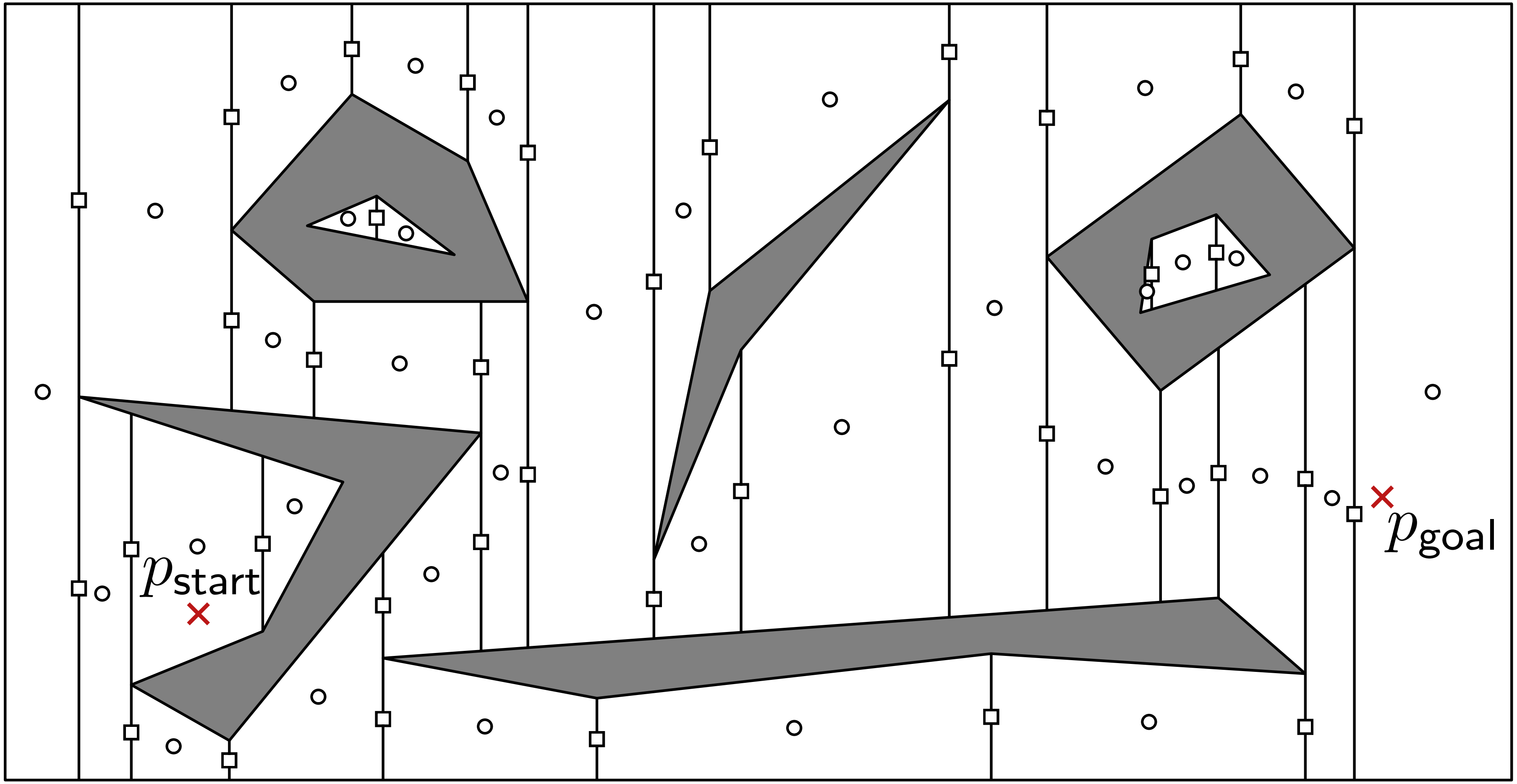
- First compute trapezoidal map

First Idea: Shortest Paths in Graphs



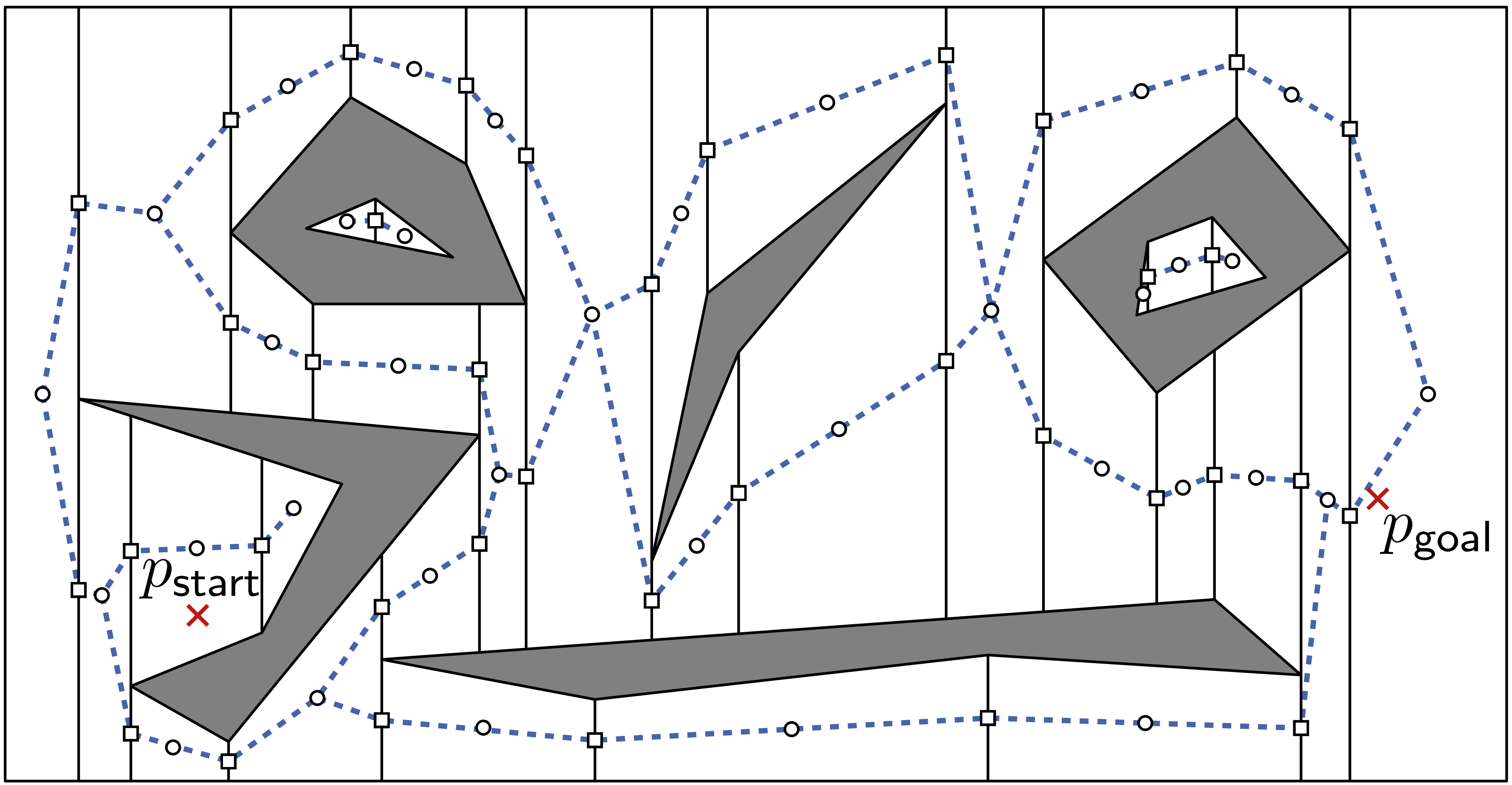
- First compute trapezoidal map
- Remove segments in obstacles

First Idea: Shortest Paths in Graphs



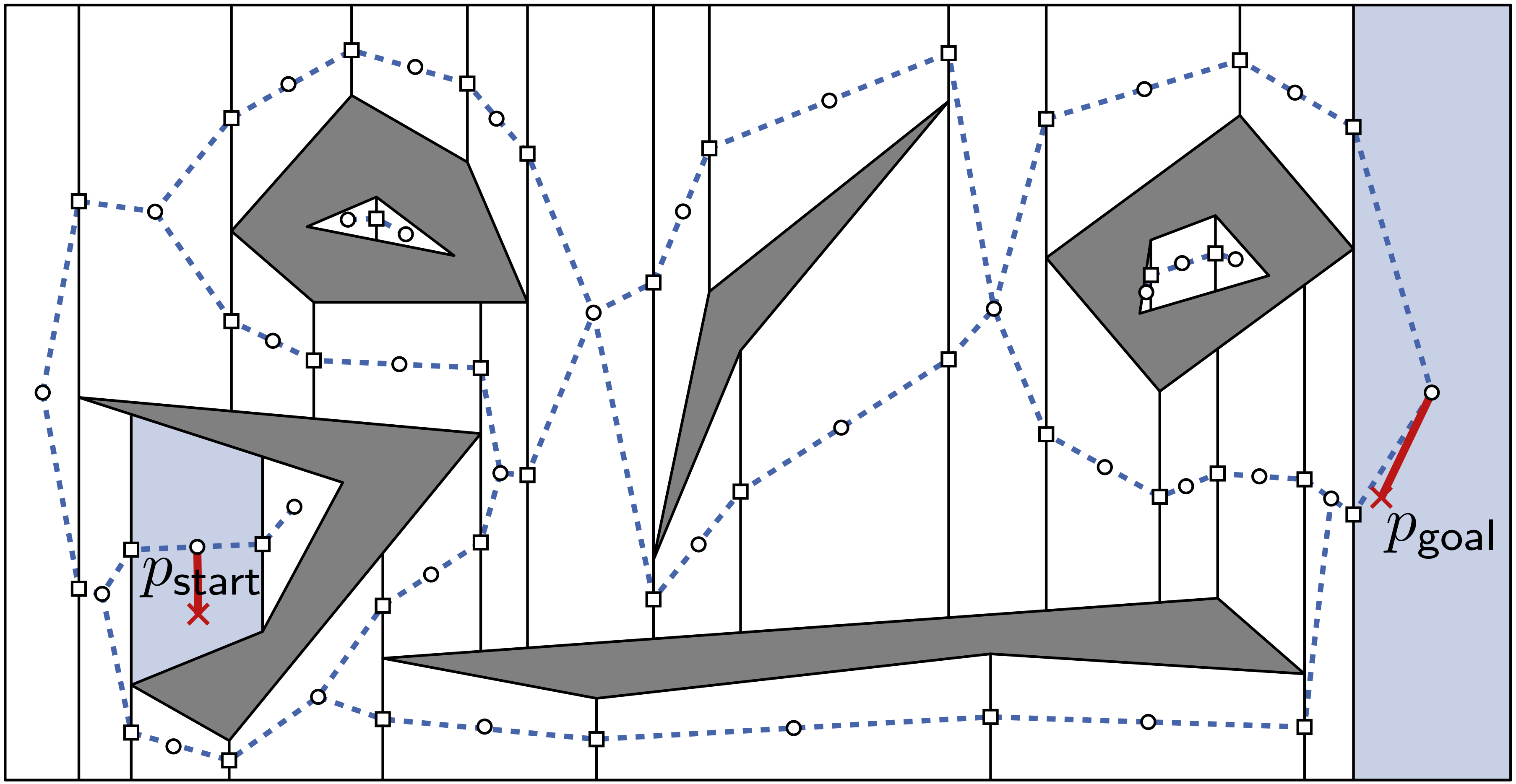
- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments

First Idea: Shortest Paths in Graphs



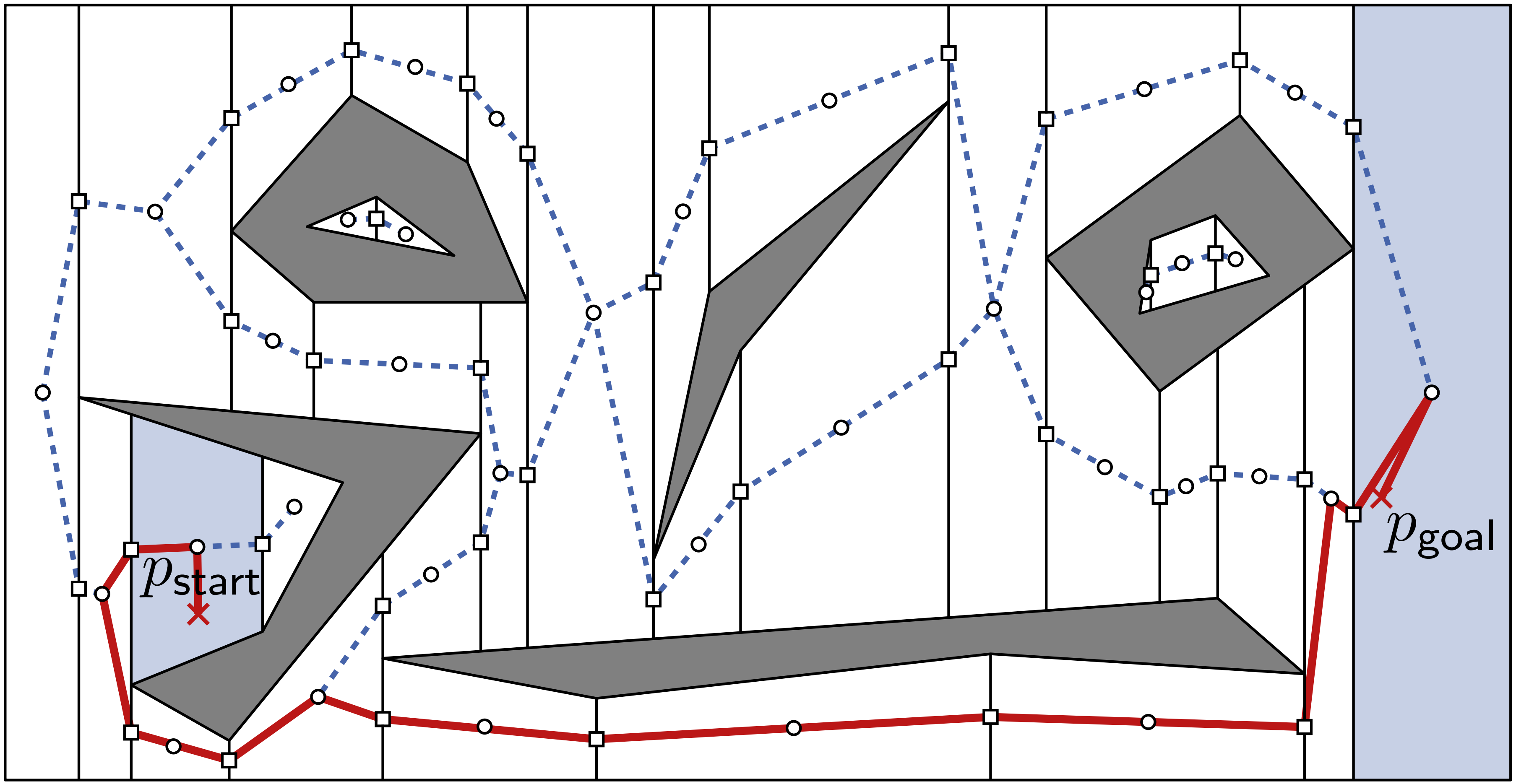
- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments
- Euclidean weighted “dual graph” G with nodes on vertical segments

First Idea: Shortest Paths in Graphs



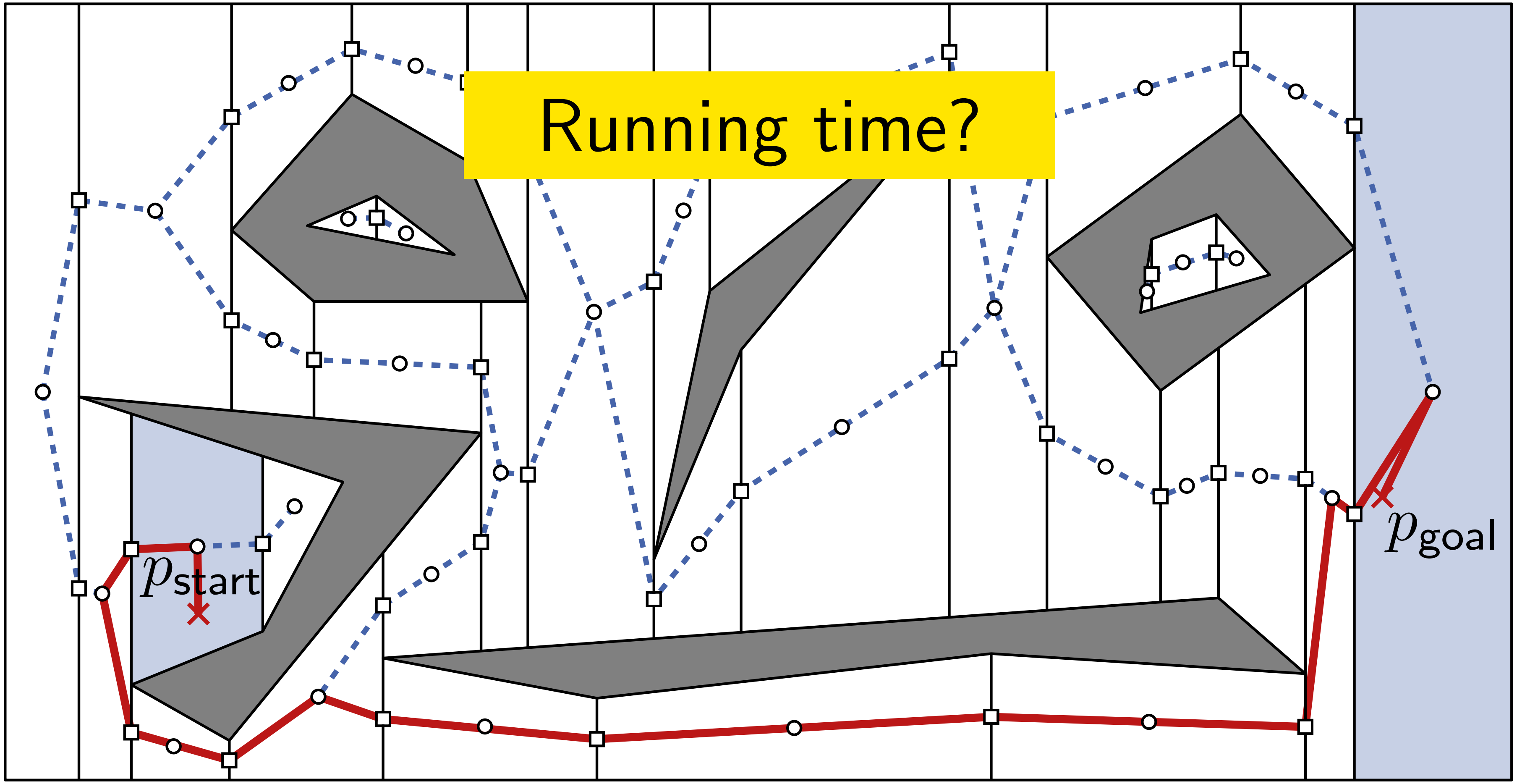
- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments
- Euclidean weighted "dual graph" G with nodes on vertical segments
- Locate start and goal

First Idea: Shortest Paths in Graphs



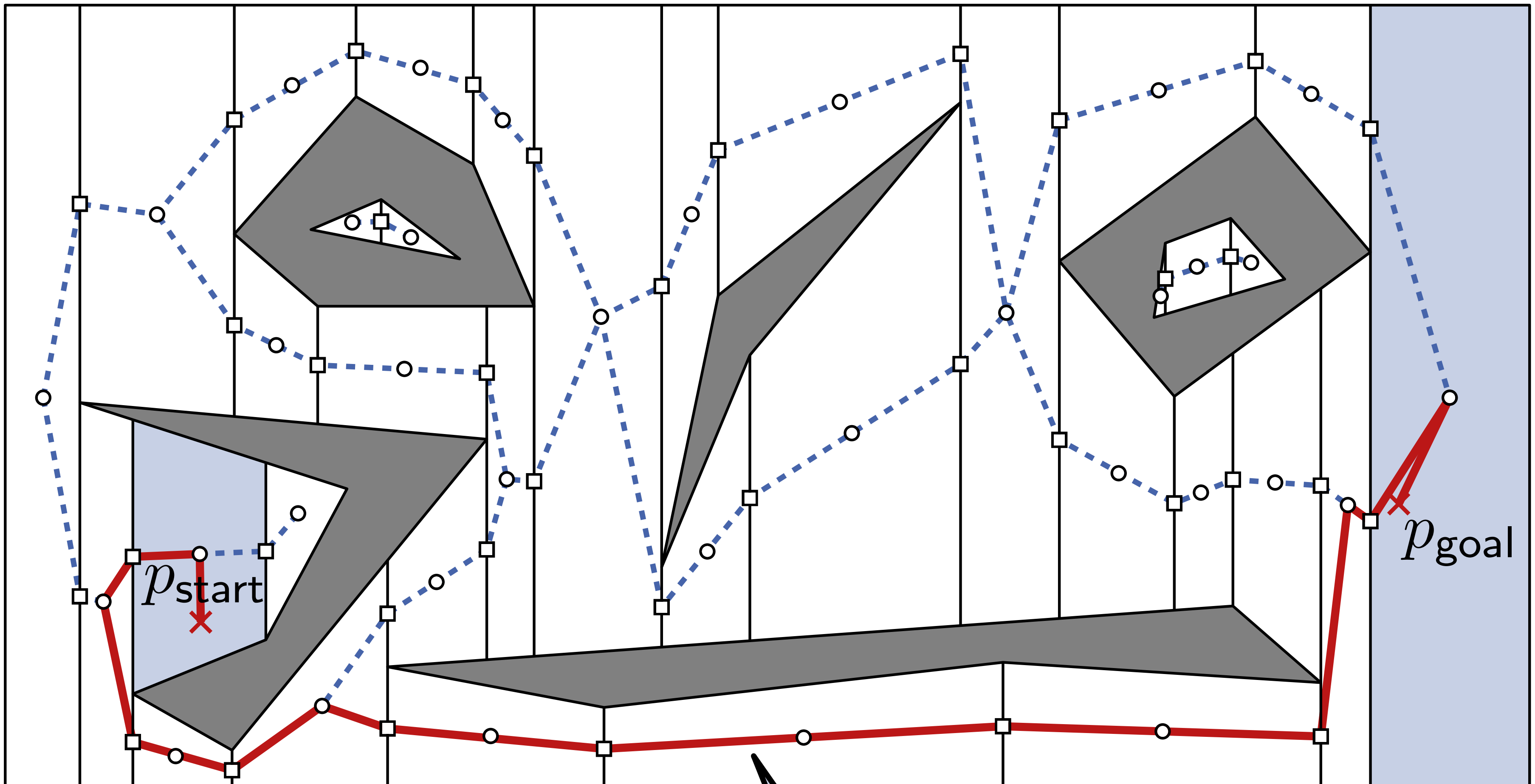
- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments
- Euclidean weighted "dual graph" G with nodes on vertical segments
- Locate start and goal
- Shortest path with Dijkstra in G

First Idea: Shortest Paths in Graphs



- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments
- Euclidean weighted “dual graph” G with nodes on vertical segments
- Locate start and goal
- Shortest path with Dijkstra in G

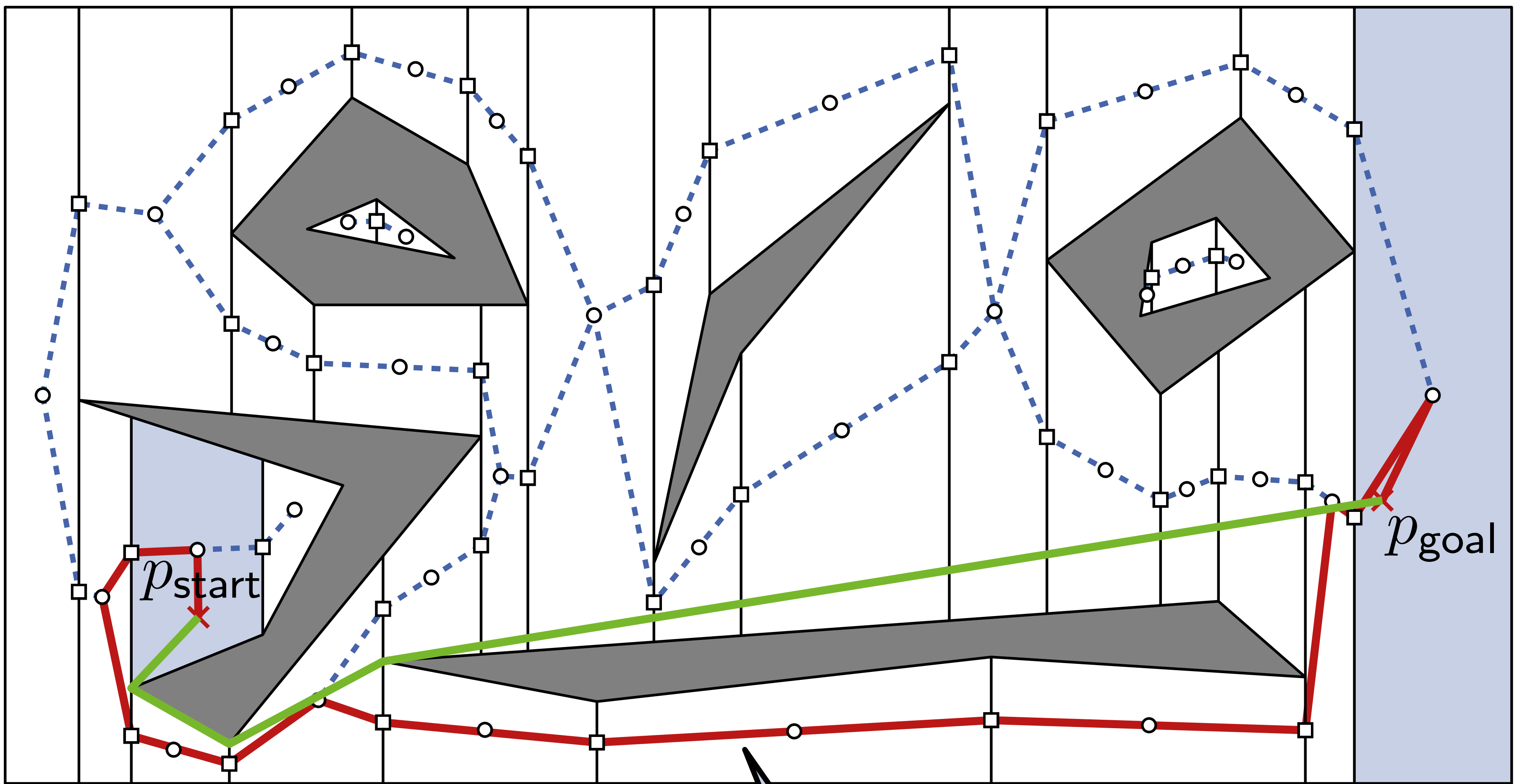
First Idea: Shortest Paths in Graphs



not the shortest path!

- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments
- Euclidean weighted "dual graph" G with nodes on vertical segments
- Locate start and goal
- Shortest path with Dijkstra in G

First Idea: Shortest Paths in Graphs

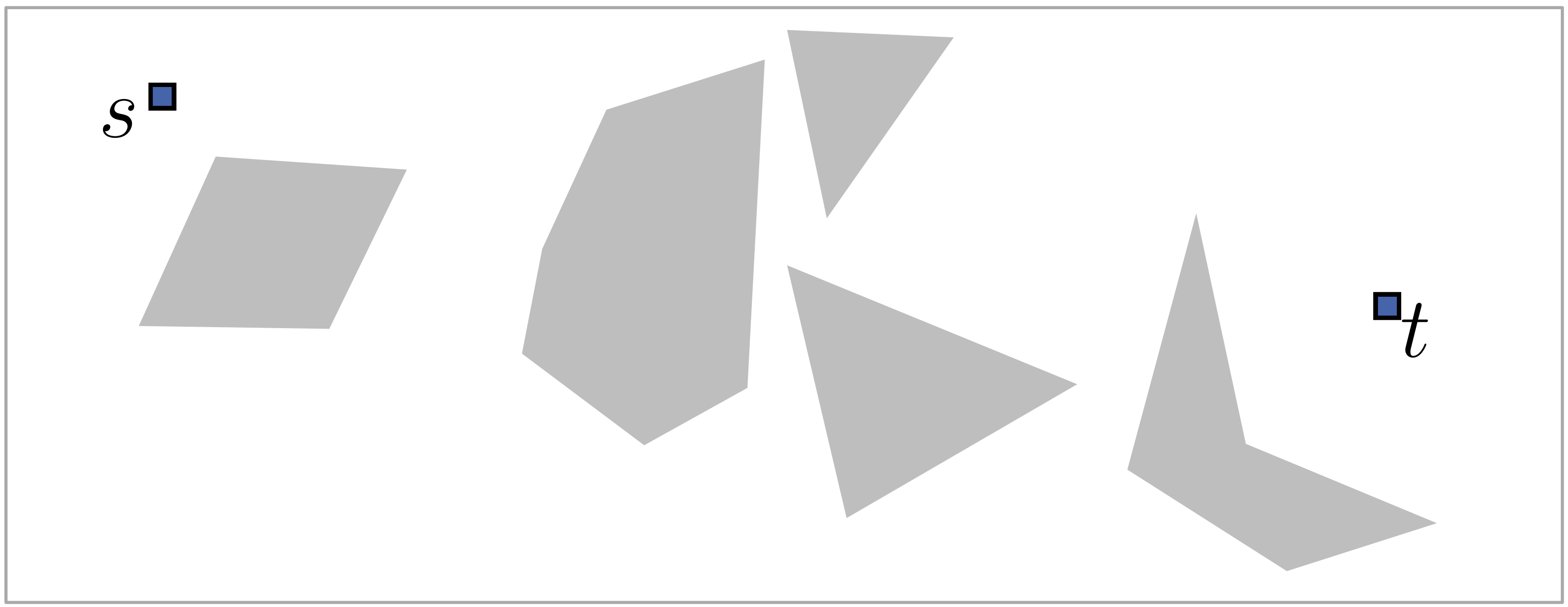


not the shortest path!

- First compute trapezoidal map
- Remove segments in obstacles
- Nodes in trapezoids and vertical line segments
- Euclidean weighted “dual graph” G with nodes on vertical segments
- Locate start and goal
- Shortest path with Dijkstra in G

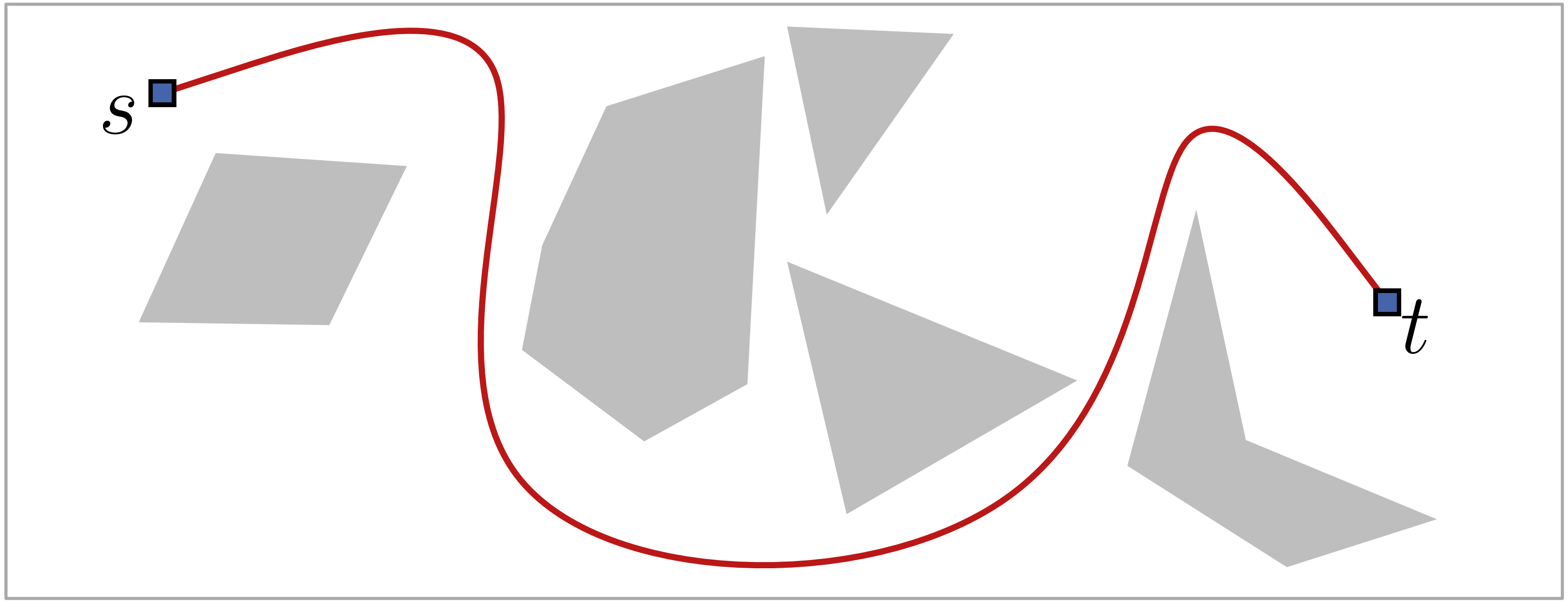
Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S



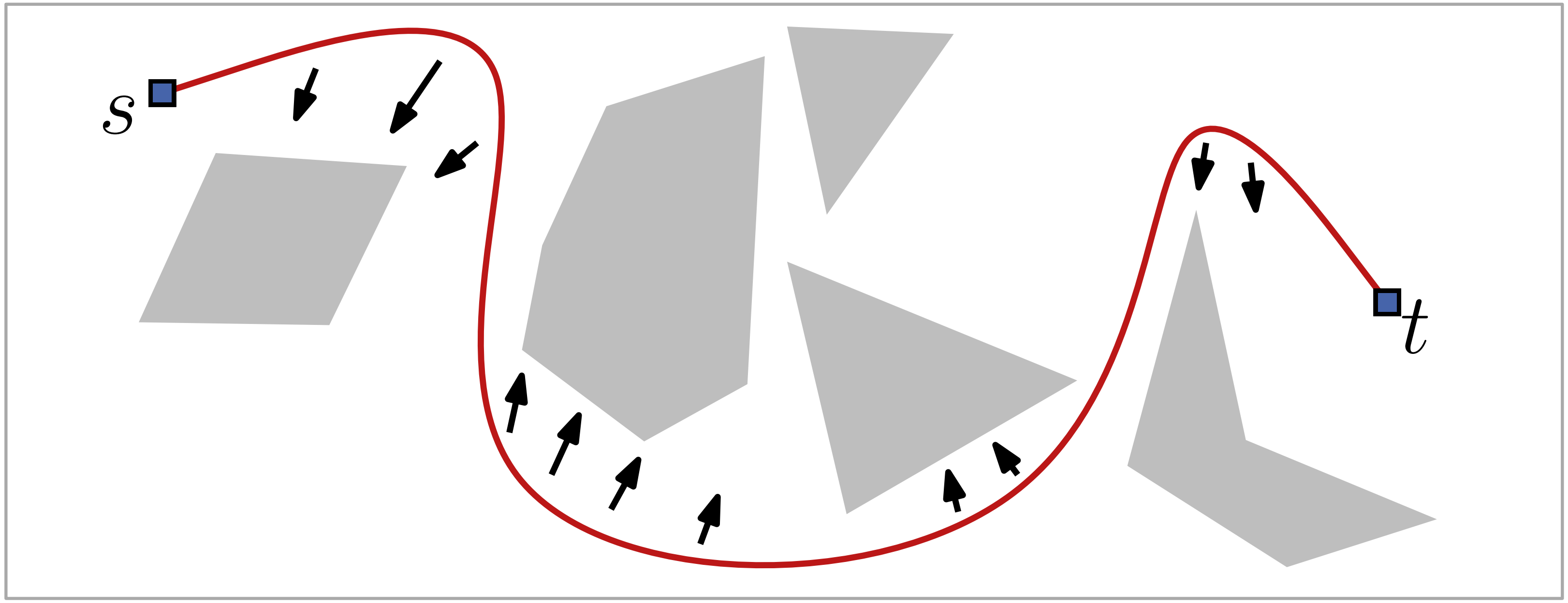
Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S
each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



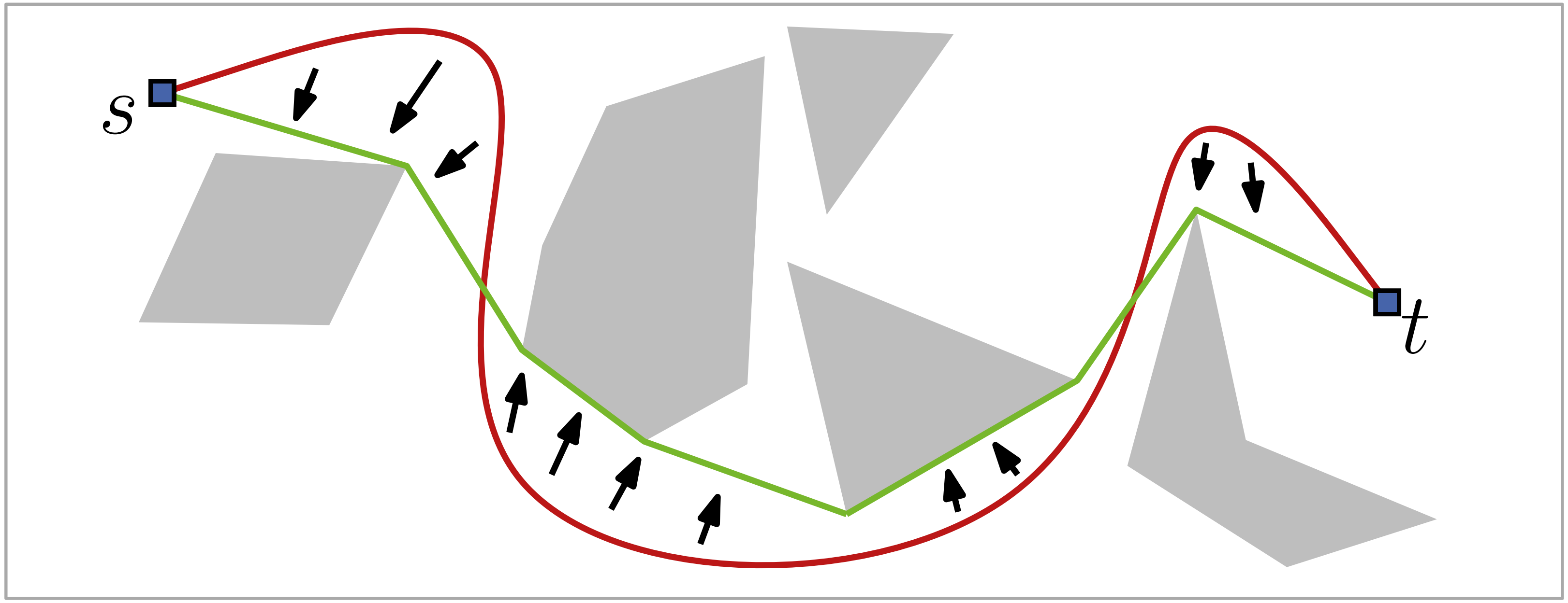
Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



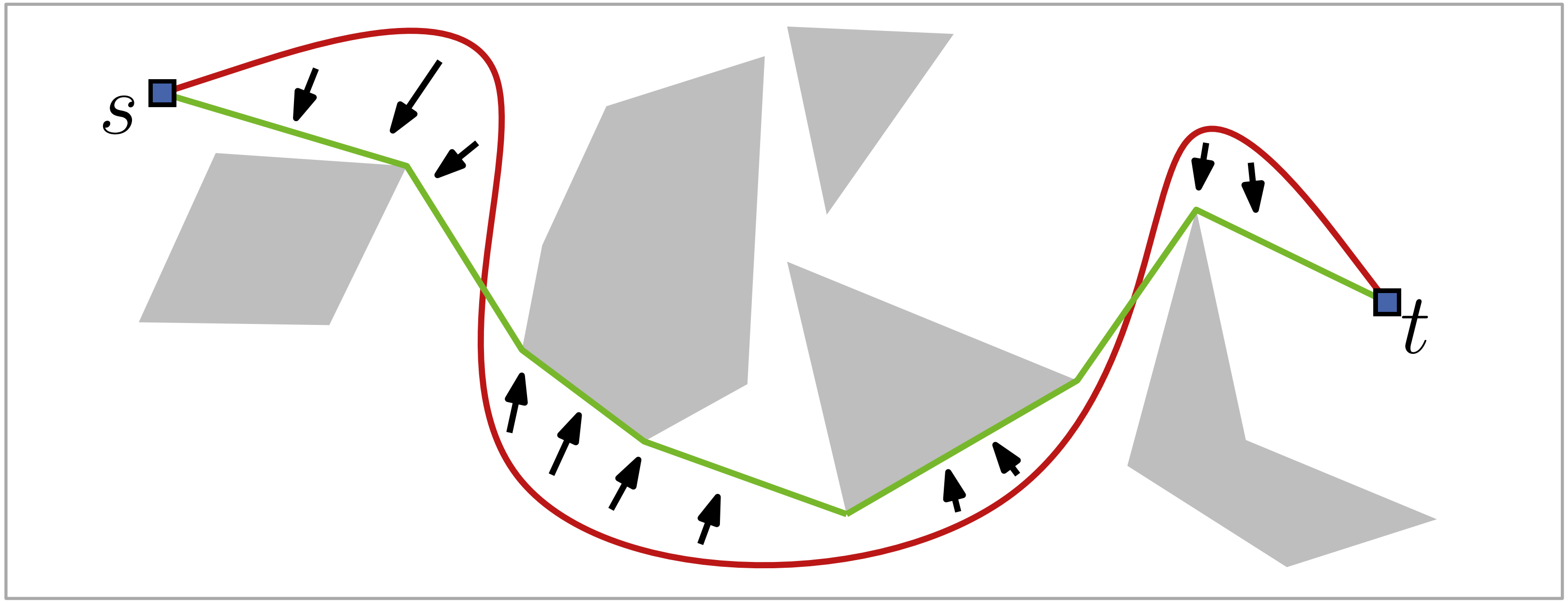
Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S
each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



Shortest Paths in Polygonal Areas

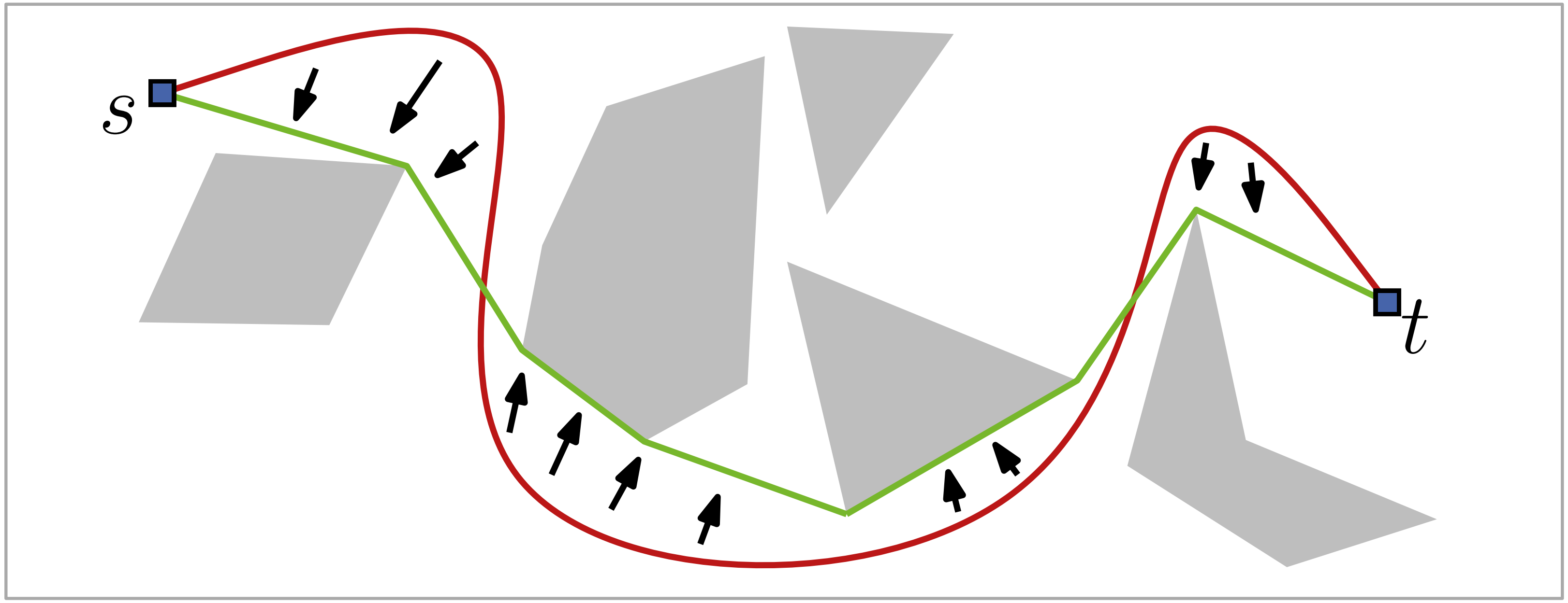
Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



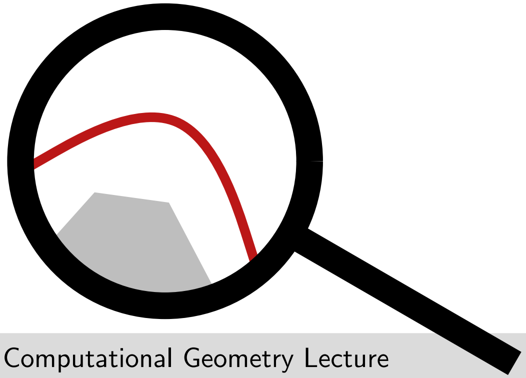
Proof sketch:

Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.

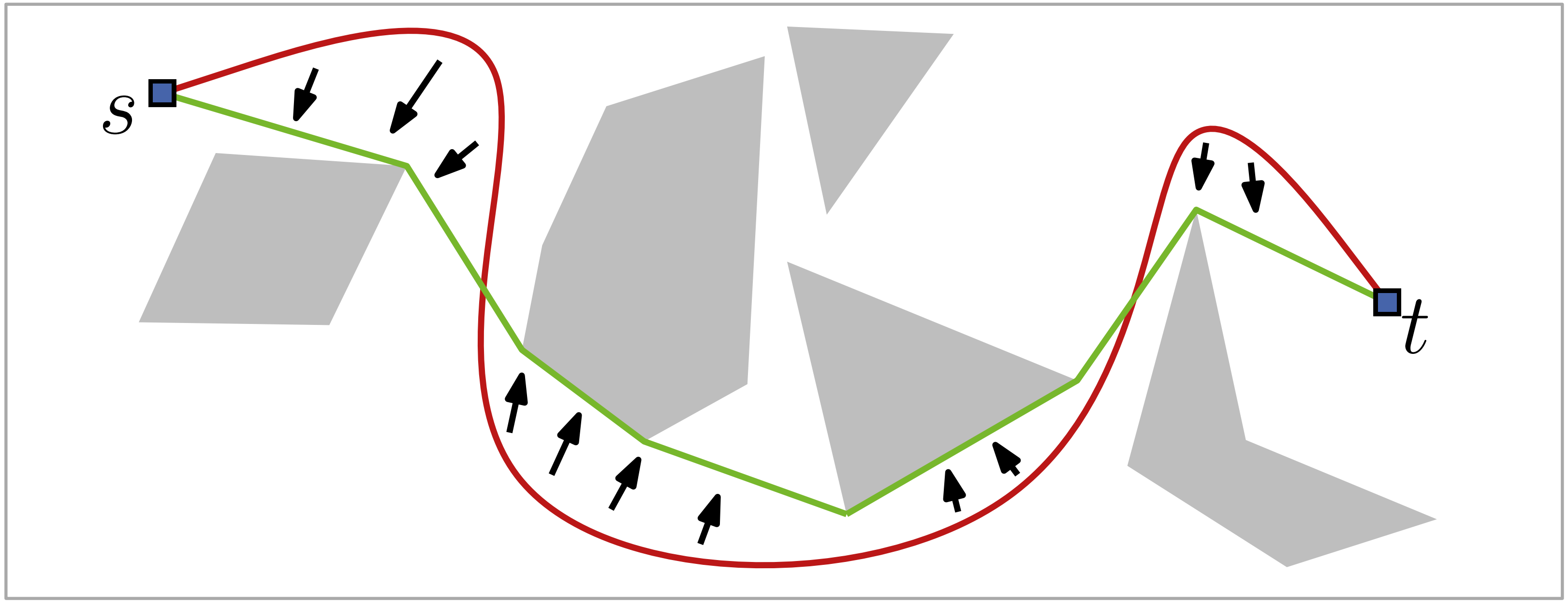


Proof sketch:

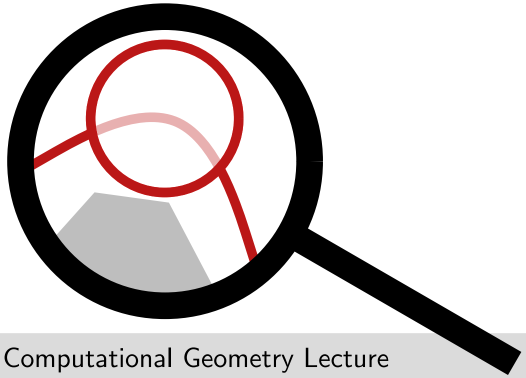


Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S
each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.

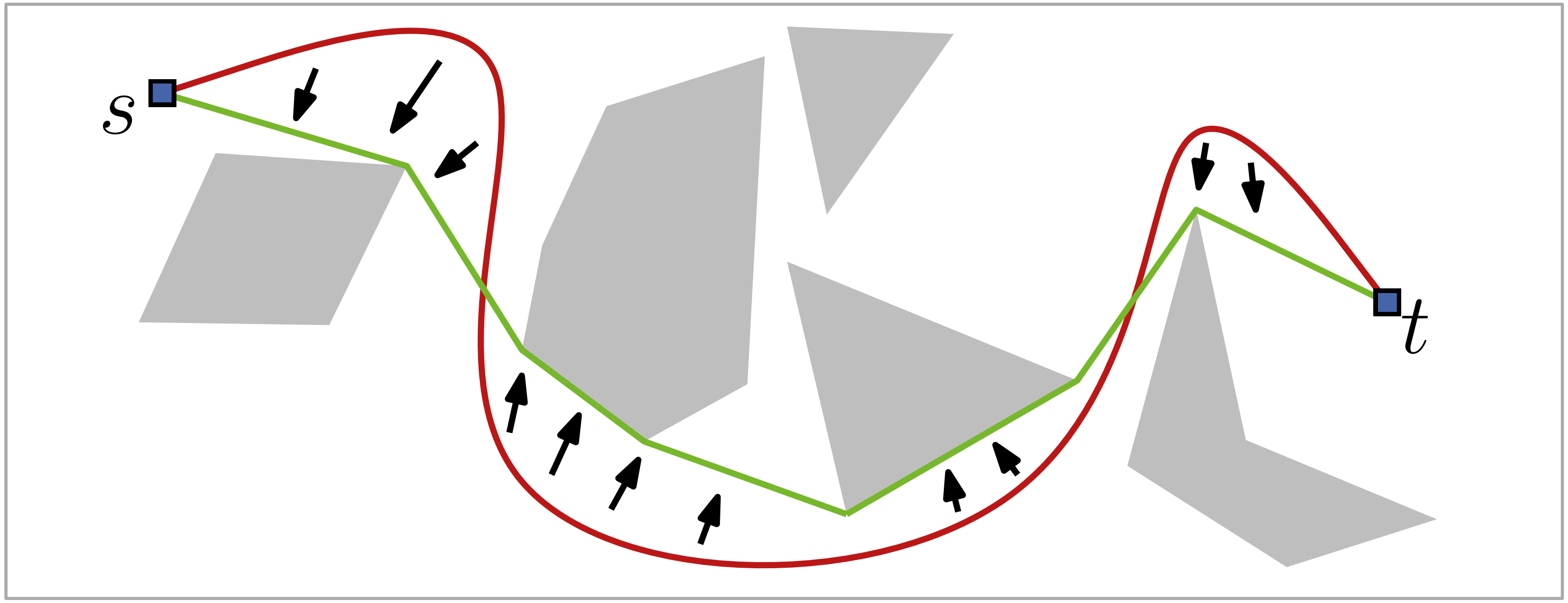


Proof sketch:

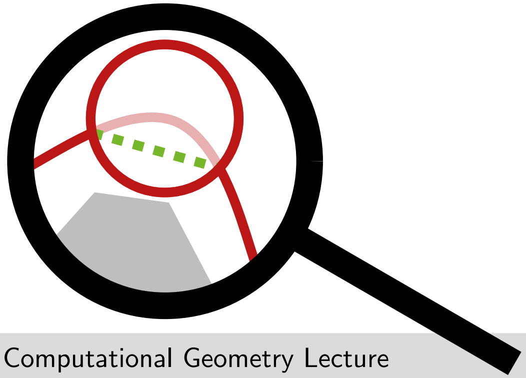


Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.

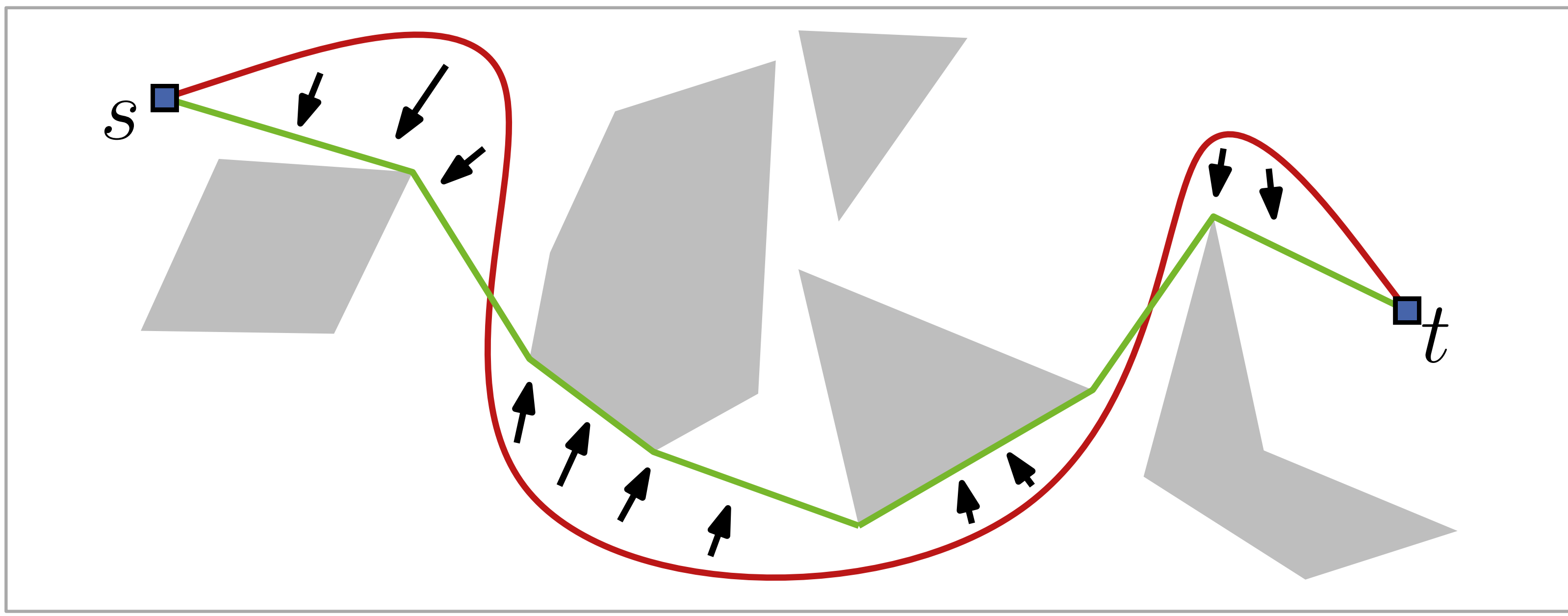


Proof sketch:



Shortest Paths in Polygonal Areas

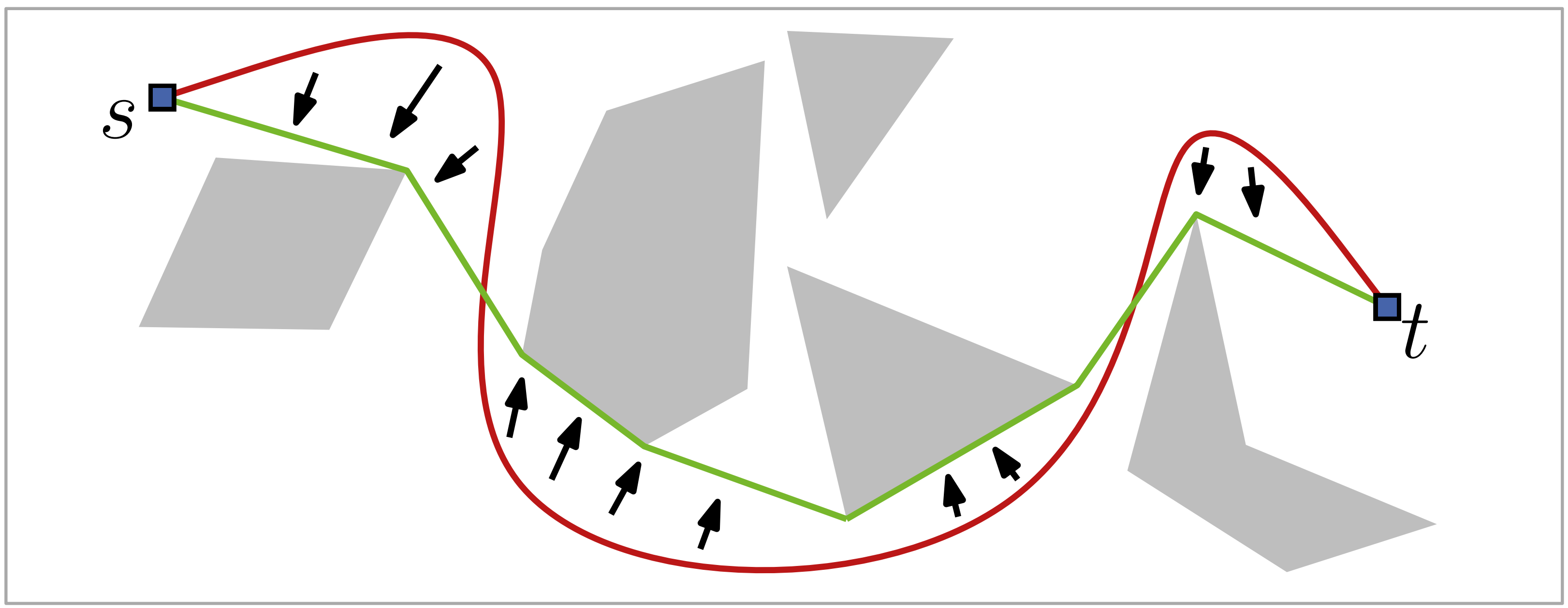
Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



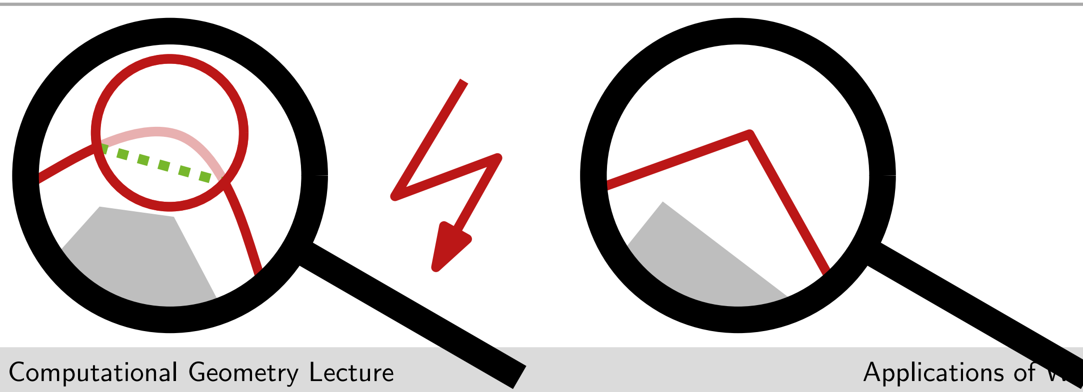
Proof sketch:

Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.

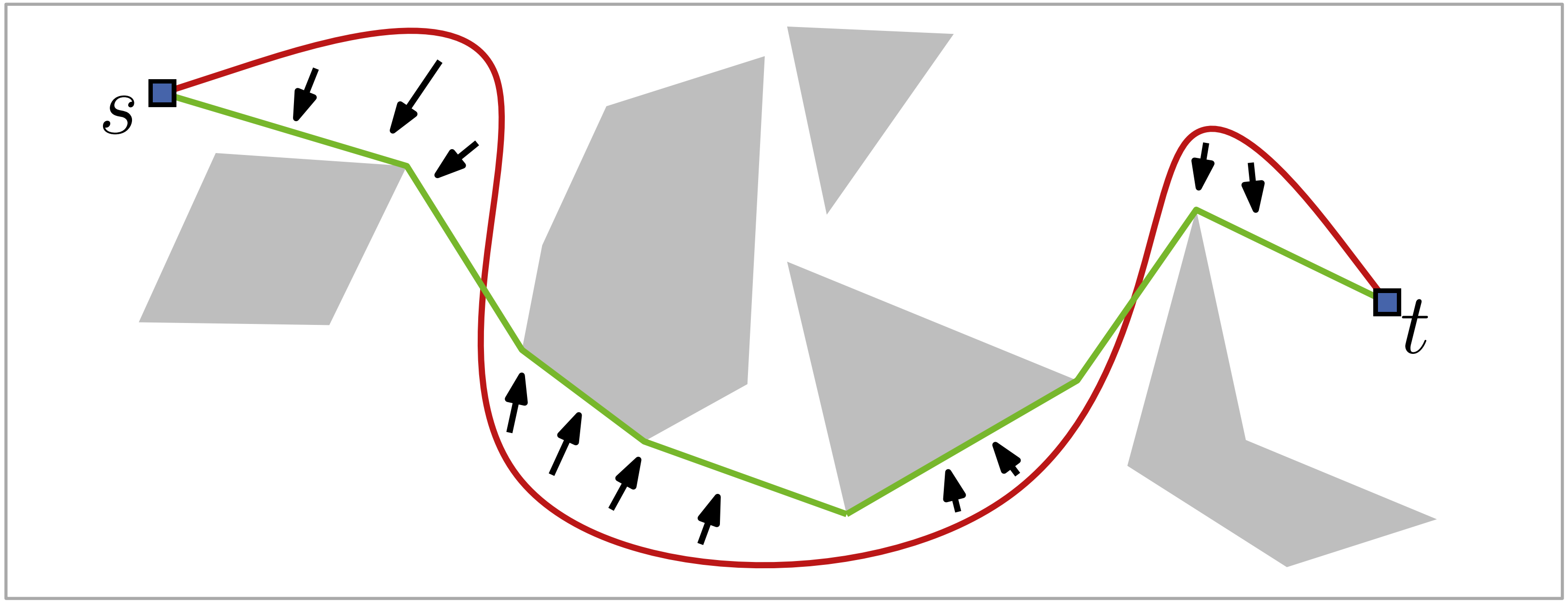


Proof sketch:

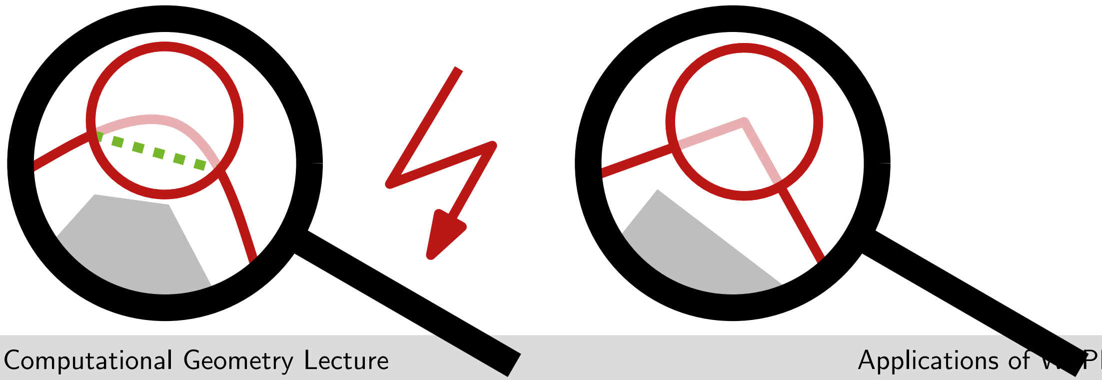


Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.

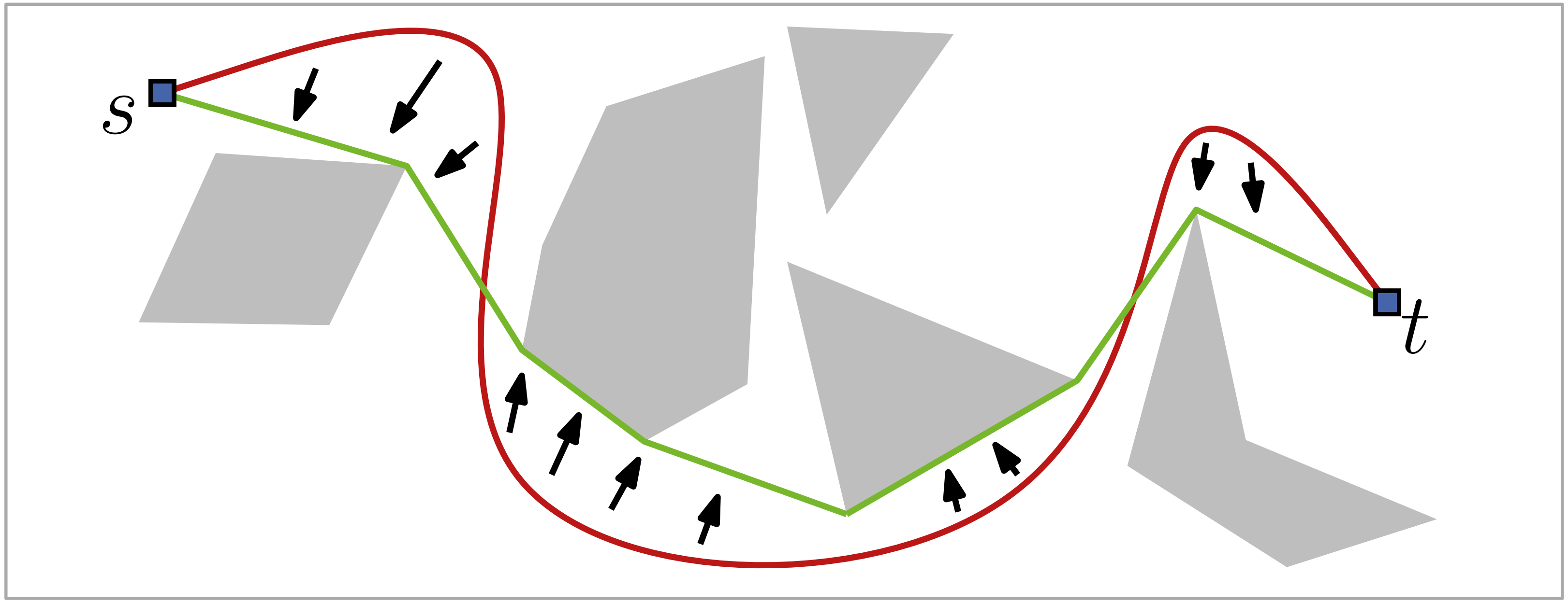


Proof sketch:

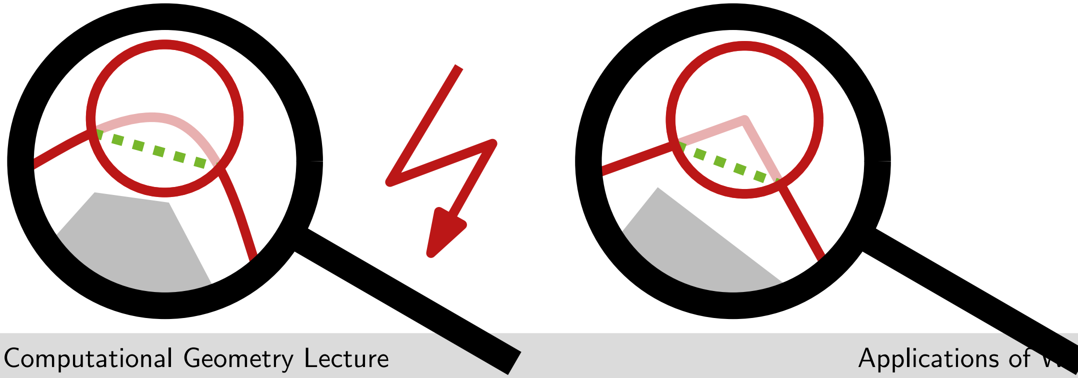


Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.

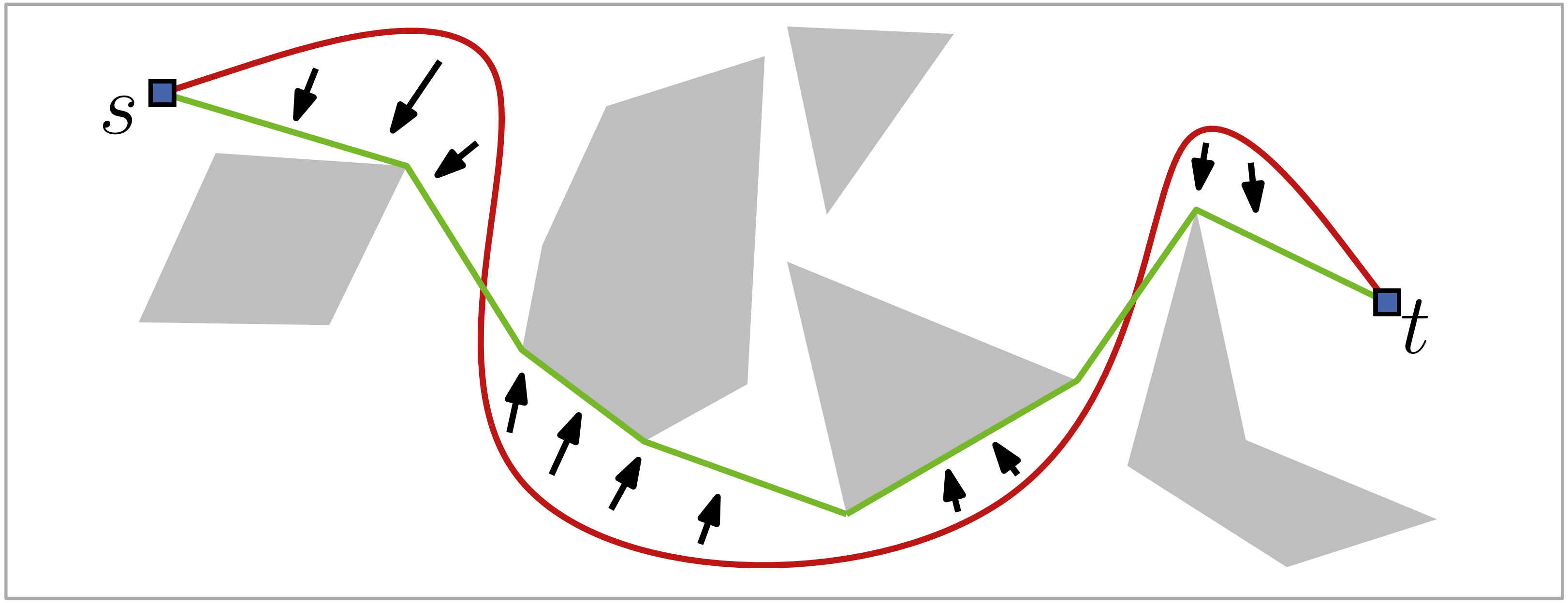


Proof sketch:

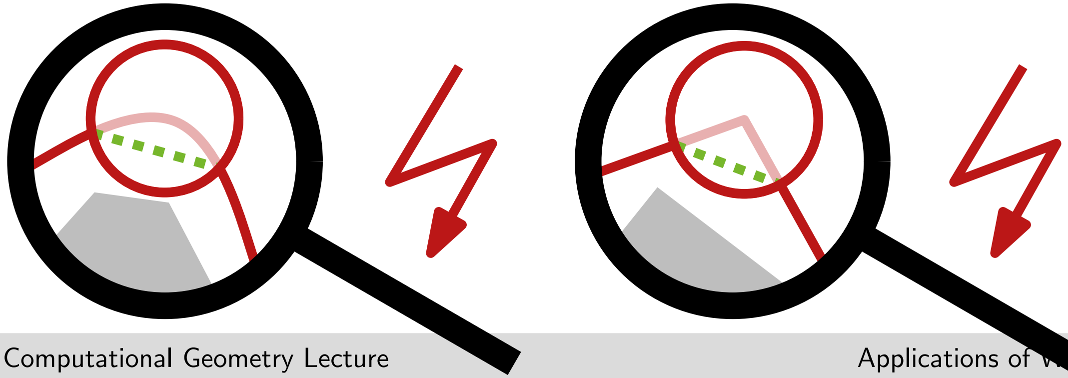


Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



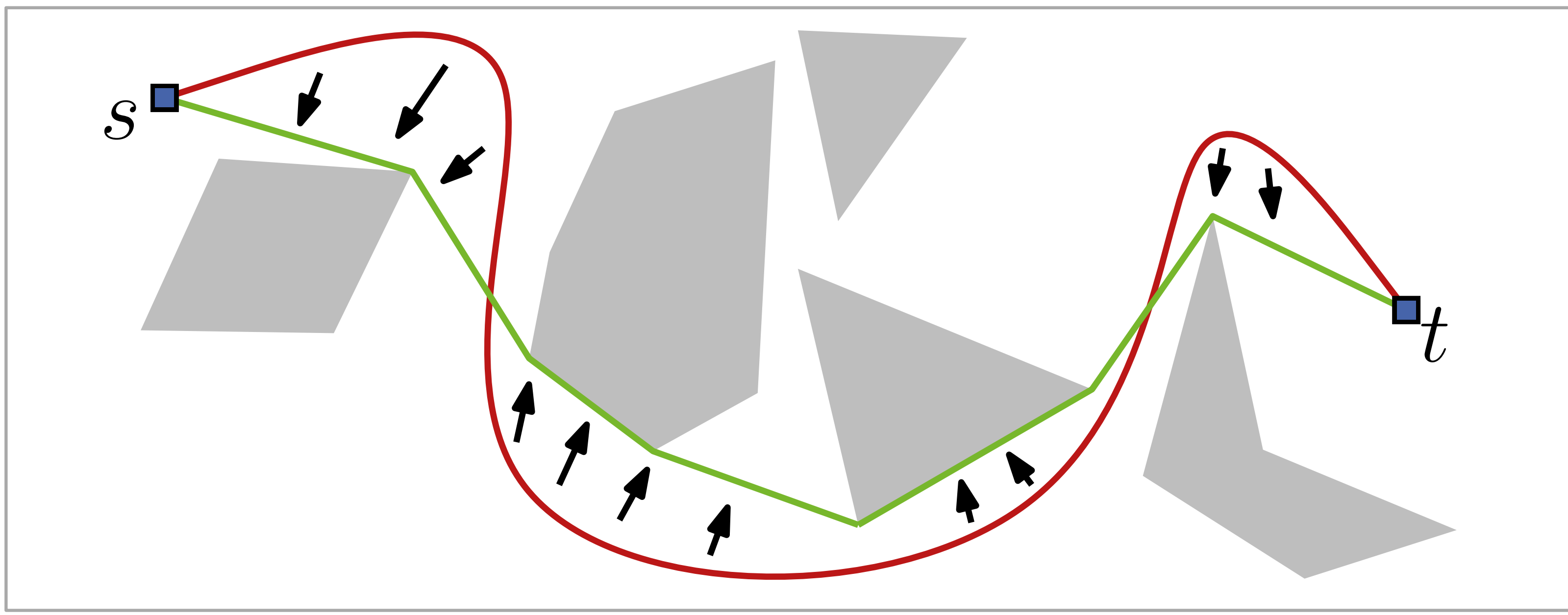
Proof sketch:



Shortest Paths in Polygonal Areas

Karlsruhe Institute of Technology

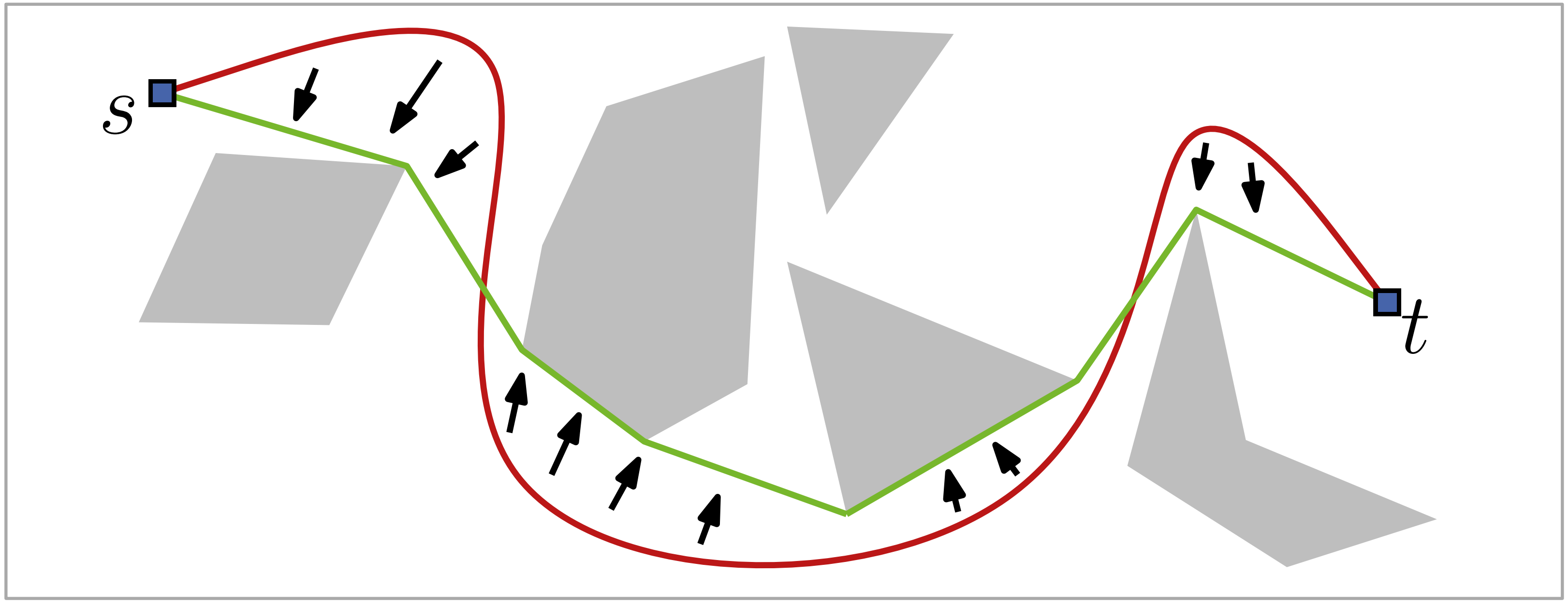
Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



Proof sketch:

Shortest Paths in Polygonal Areas

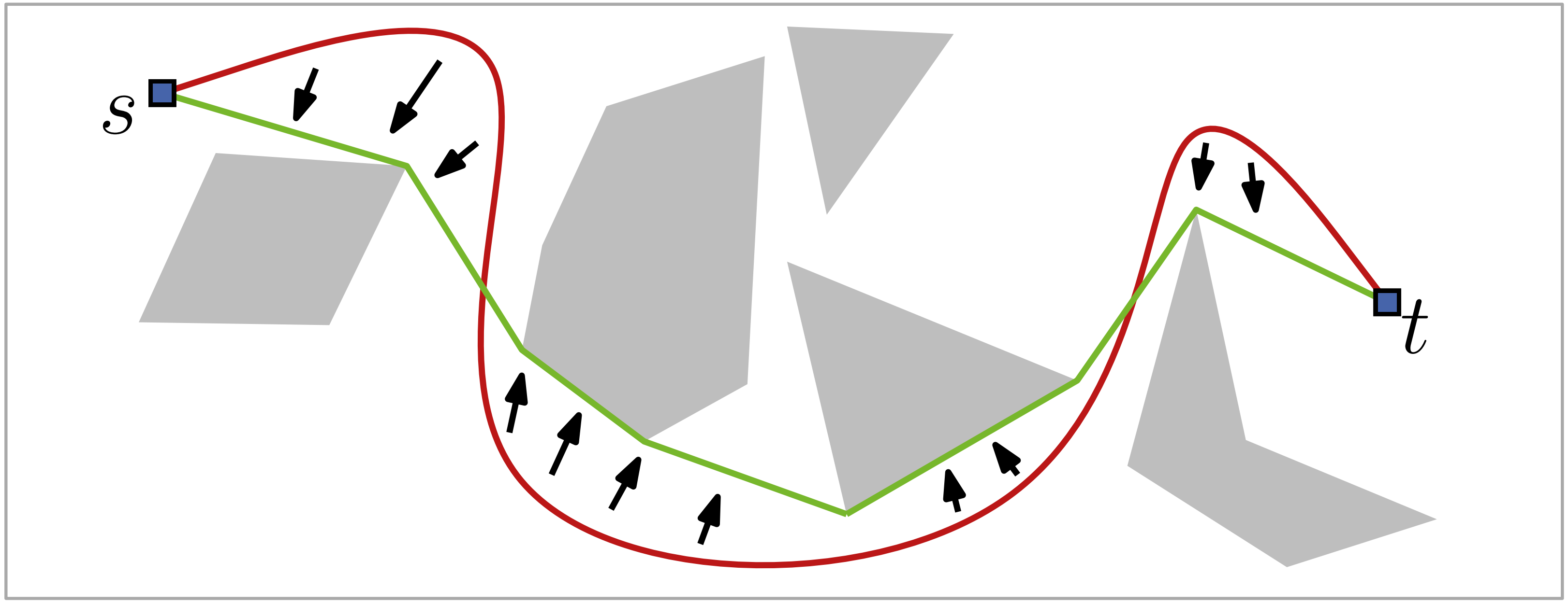
Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



Proof sketch:

Shortest Paths in Polygonal Areas

Lemma 1: For a set S of disjoint open polygons in $\mathbb{R}^2$ and two points s and t not in S each shortest st-path in $\mathbb{R}^2 \setminus \bigcup S$ is a polygonal path whose internal vertices are vertices of S.



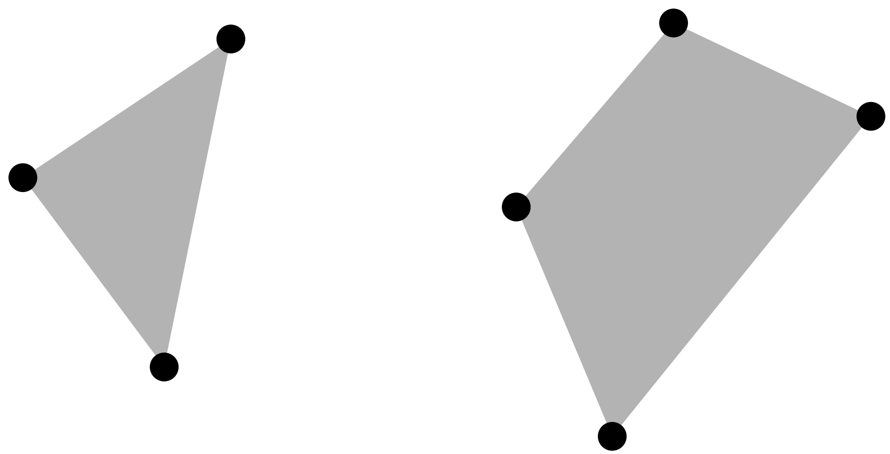
Proof sketch:

Visibility Graph

Given a set S of disjoint open polygons...

Visibility Graph

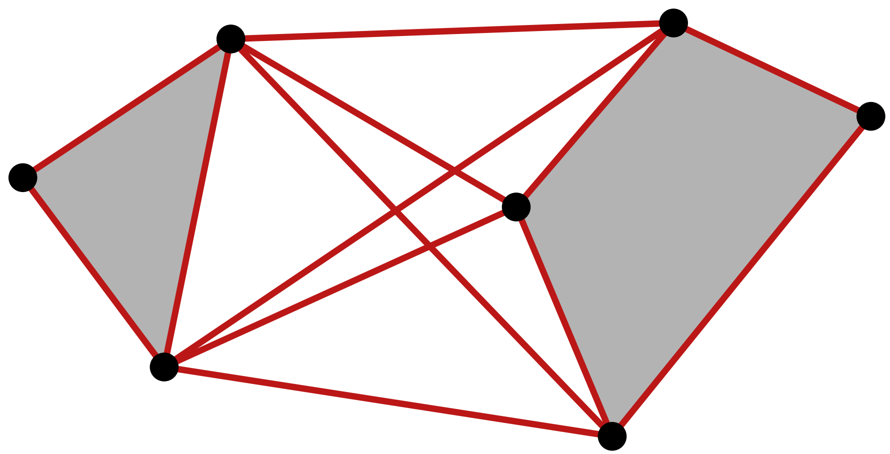
Given a set S of disjoint open polygons...



...with point set $V(S)$.

Visibility Graph

Given a set S of disjoint open polygons...

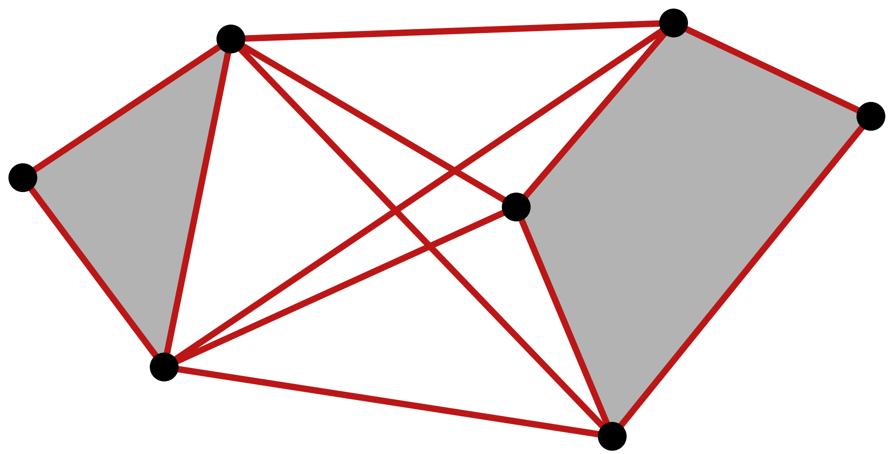


...with point set $V(S)$.

Def.: Then $G_{\mathsf{vis}}(S) = (V(S), E_{\mathsf{vis}}(S))$ is the **visibility graph** of S with $E_{\mathsf{vis}}(S) = \{uv \mid u, v \in V(S)$ and u *sees* $v\}$ und $w(uv) = |uv|$.

Visibility Graph

Given a set S of disjoint open polygons...

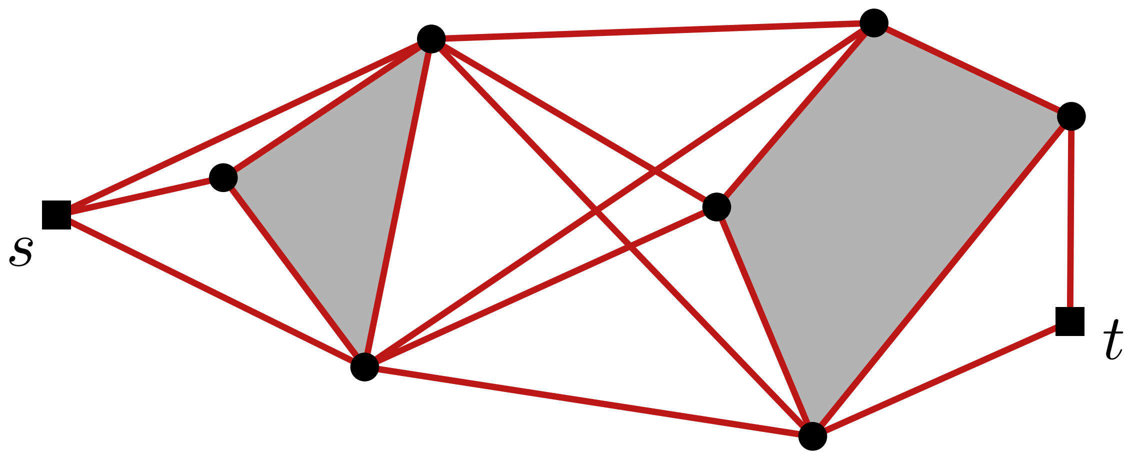


...with point set $V(S)$.

Def.: Then $G_{\text{vis}}(S) = (V(S), E_{\text{vis}}(S))$ is the **visibility graph** of S with $E_{\text{vis}}(S) = \{uv \mid u, v \in V(S) \text{ and } u \textit{ sees } v\}$ und $w(uv) = |uv|$.
Where u **sees** v $:\Leftrightarrow \overline{uv} \cap \bigcup S = \emptyset$

Visibility Graph

Given a set S of disjoint open polygons...



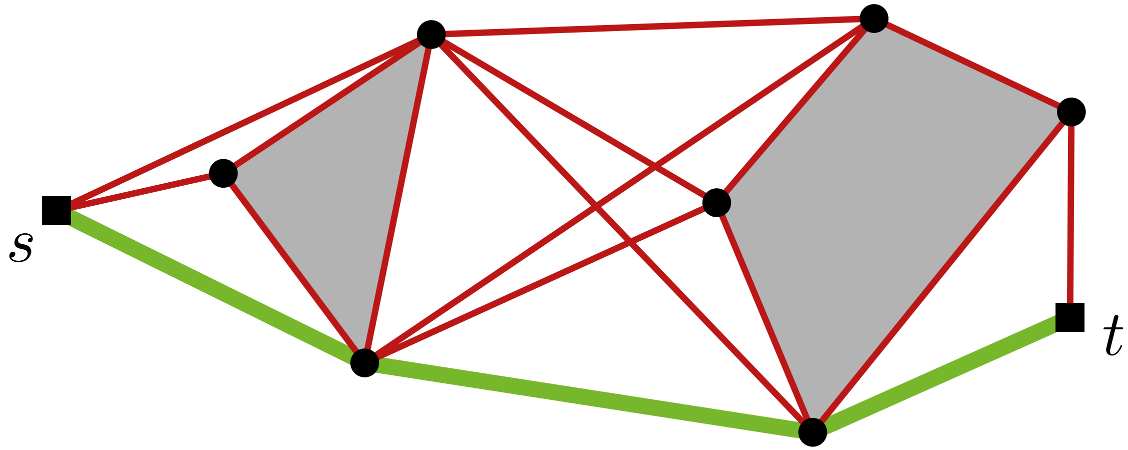
...with point set $V(S)$.

Def.: Then $G_{\text{vis}}(S) = (V(S), E_{\text{vis}}(S))$ is the **visibility graph** of S with $E_{\text{vis}}(S) = \{uv \mid u, v \in V(S) \text{ and } u \textit{ sees } v\}$ und $w(uv) = |uv|$.
Where u **sees** $v :\Leftrightarrow \overline{uv} \cap \bigcup S = \emptyset$

Define $S^\star = S \cup \{s, t\}$ and $G_{\text{vis}}(S^\star)$ analogously.

Visibility Graph

Given a set S of disjoint open polygons...



...with point set $V(S)$.

Def.: Then $G_{\text{vis}}(S) = (V(S), E_{\text{vis}}(S))$ is the **visibility graph** of S with $E_{\text{vis}}(S) = \{uv \mid u, v \in V(S)$ and u *sees* $v\}$ und $w(uv) = |uv|$.
Where u **sees** $v :\Leftrightarrow \overline{uv} \cap \bigcup S = \emptyset$

Define $S^\star = S \cup \{s, t\}$ and $G_{\text{vis}}(S^\star)$ analogously.

Lemma 1
$\Rightarrow$

> A shortest st-path in $\mathbb{R}^2$ avoiding obstacles in S is equivalent to a shortest st-path in $G_{\text{vis}}(S^\star)$.

Algorithm

ShortestPath(S, s, t)

Input: Obstacles S, points $s, t \in \mathbb{R}^2 \setminus \bigcup S$
Output: Shortest collision-free st-path in S

```
G_vis ← VisibilityGraph(S ∪ {s, t})
foreach uv ∈ E_vis do w(uv) ← |uv|
return Dijkstra(G_vis, w, s, t)
```

Algorithm

ShortestPath(S, s, t) $\boxed{n = |V(S)|, m = |E_{\text{vis}}(S)|}$

Input: Obstacles S, points $s, t \in \mathbb{R}^2 \setminus \bigcup S$
Output: Shortest collision-free st-path in S

$G_{\text{vis}} \leftarrow$ VisibilityGraph$(S \cup \{s, t\})$?
foreach $uv \in E_{\text{vis}}$ **do** $w(uv) \leftarrow |uv|$ $O(m)$
return Dijkstra$(G_{\text{vis}}, w, s, t)$ $O(n \log n + m)$

Algorithm

ShortestPath(S, s, t)

$\boxed{n = |V(S)|, m = |E_{\mathsf{vis}}(S)|}$

Input: Obstacles S, points $s, t \in \mathbb{R}^2 \setminus \bigcup S$
Output: Shortest collision-free st-path in S

$G_{\mathsf{vis}} \leftarrow$ VisibilityGraph$(S \cup \{s, t\})$ — $O(n^2 \log n)$
foreach $uv \in E_{\mathsf{vis}}$ **do** $w(uv) \leftarrow |uv|$ — $O(m)$
return Dijkstra$(G_{\mathsf{vis}}, w, s, t)$ — $O(n \log n + m)$

Total: $O(n^2 \log n)$

Thm 1: A shortest st-path in an area with polygonal obstacles with n edges can be computed in $O(n^2 \log n)$ time.

Computing a Visibility Graph

VisibilityGraph(S)

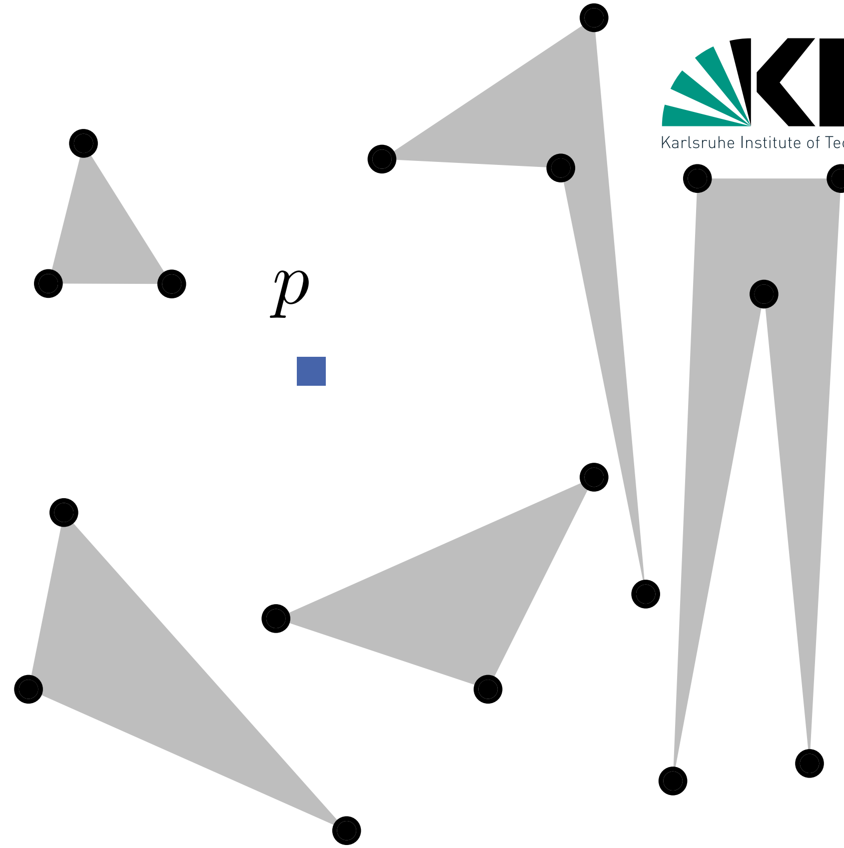
Input: Set of disjoint polygons S

Output: Visibility graph $G_{\text{vis}}(S)$

```
E ← ∅
foreach v ∈ V(S) do
    W ← VisibleVertices(v, S)
    E ← E ∪ {vw | w ∈ W}
return (V(S), E)
```

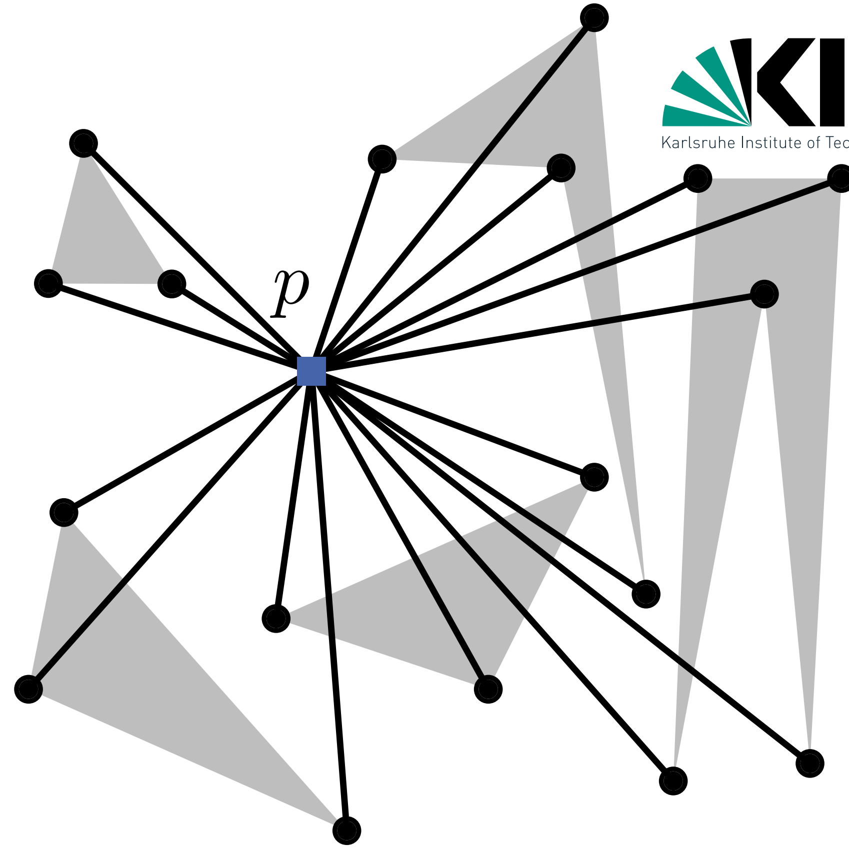
Computing Visible Nodes

VisibleVertices(p, S)



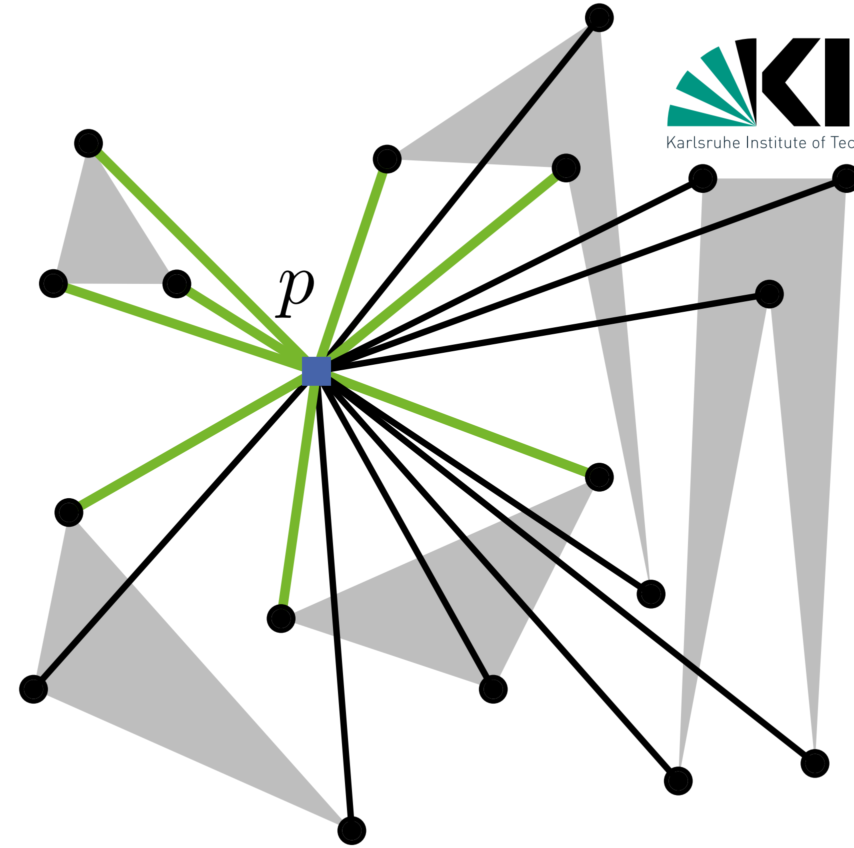
Computing Visible Nodes

VisibleVertices(p, S)



Computing Visible Nodes

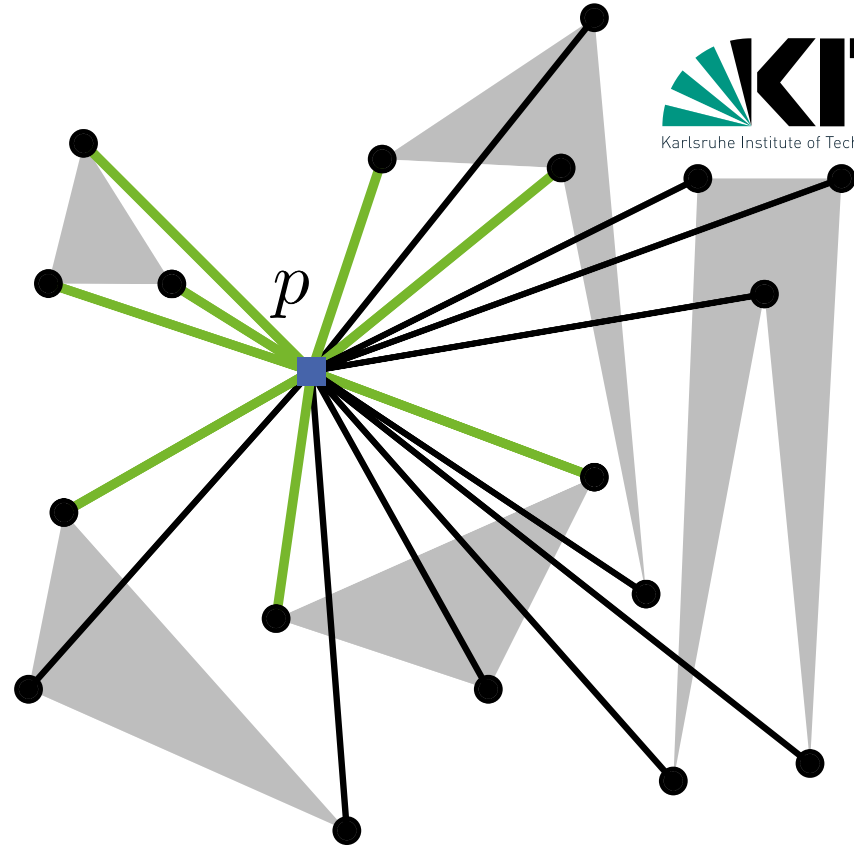
VisibleVertices(p, S)



Computing Visible Nodes

VisibleVertices(p, S)

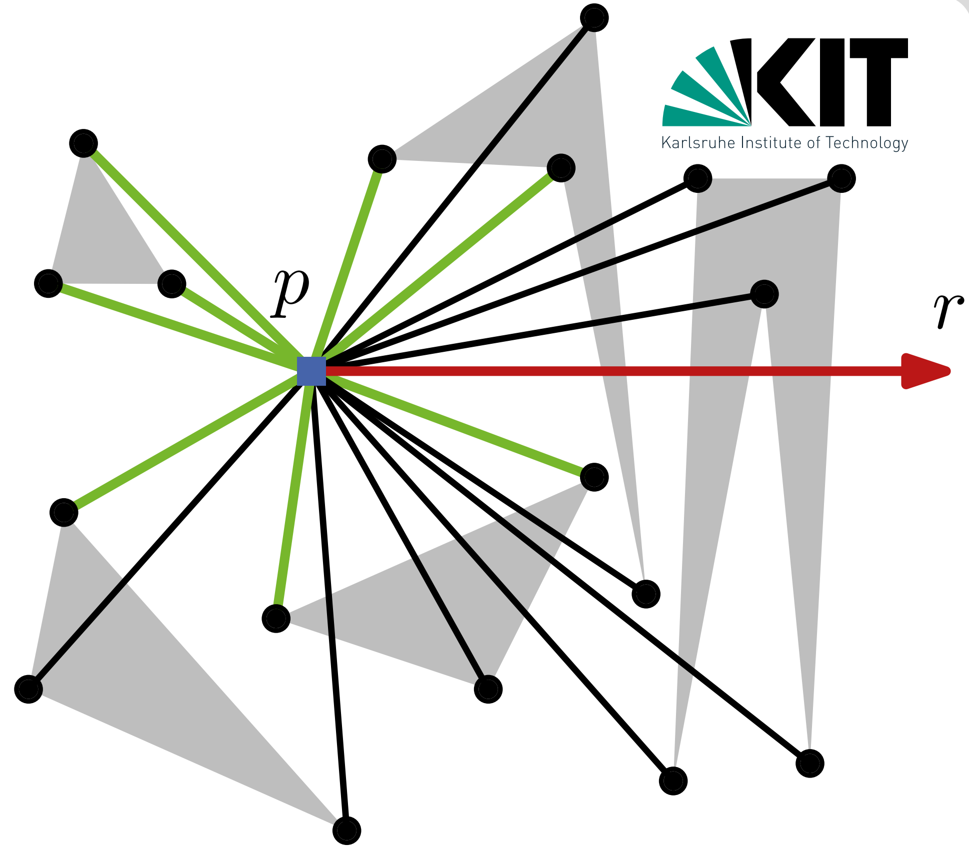
Problem: Given p and S, find in $O(n \log n)$ time all nodes that p sees in $V(S)$!



Computing Visible Nodes

VisibleVertices(p, S)

$$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$$

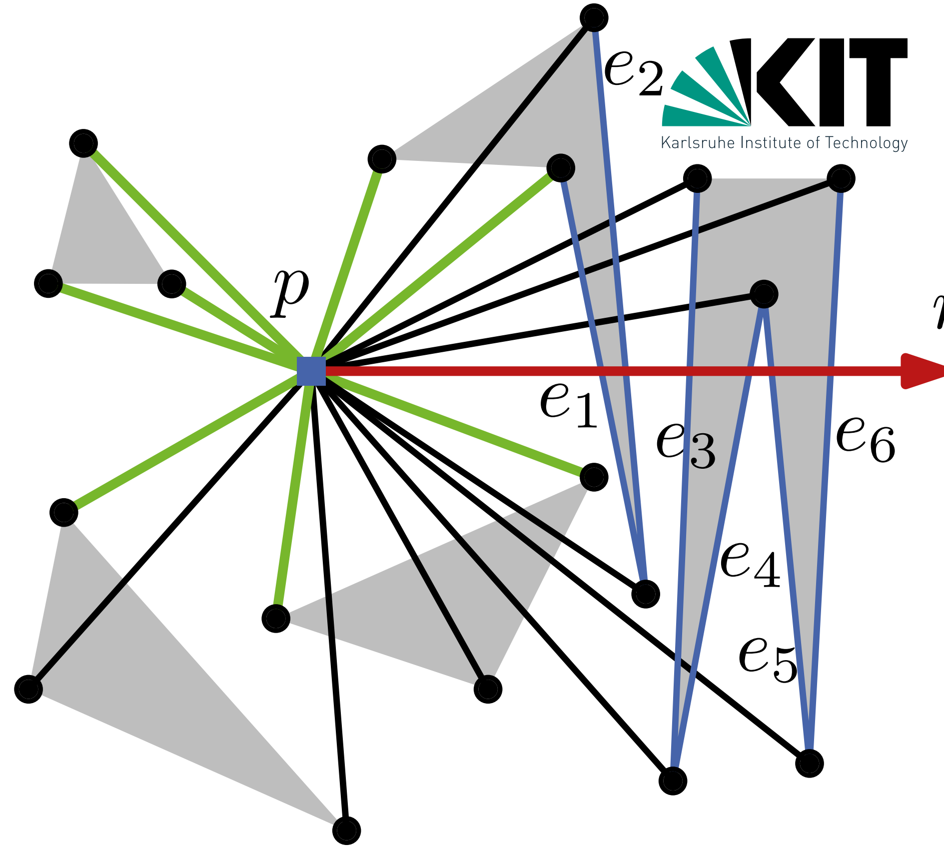


Computing Visible Nodes

VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$



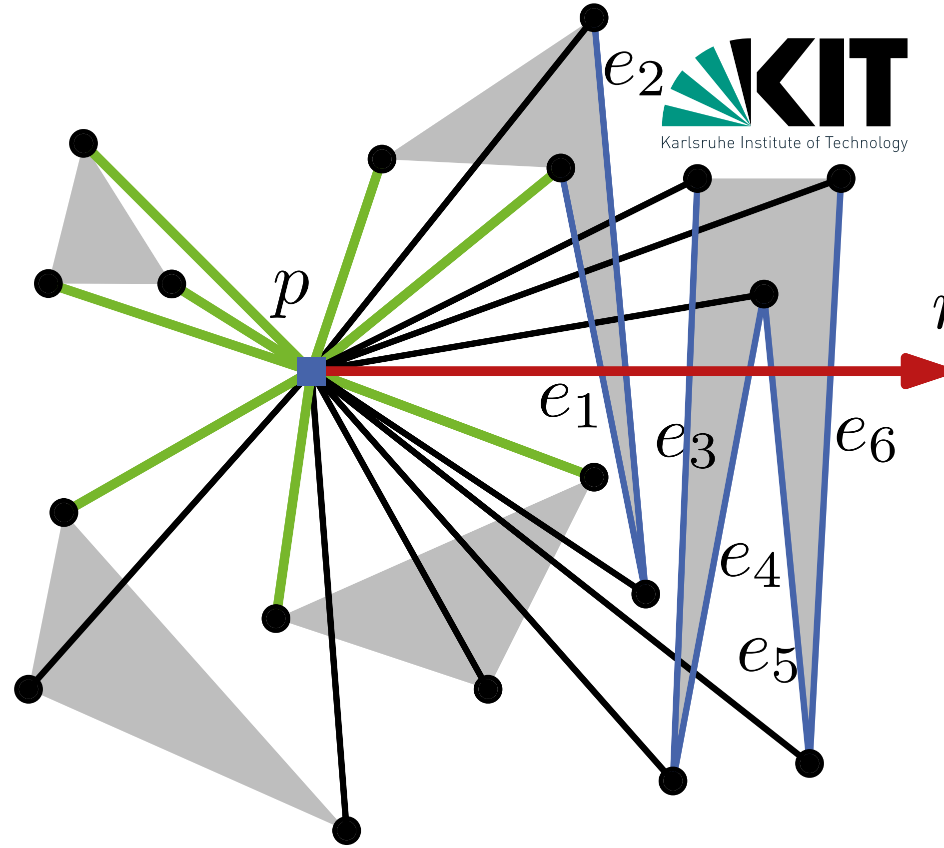
Computing Visible Nodes

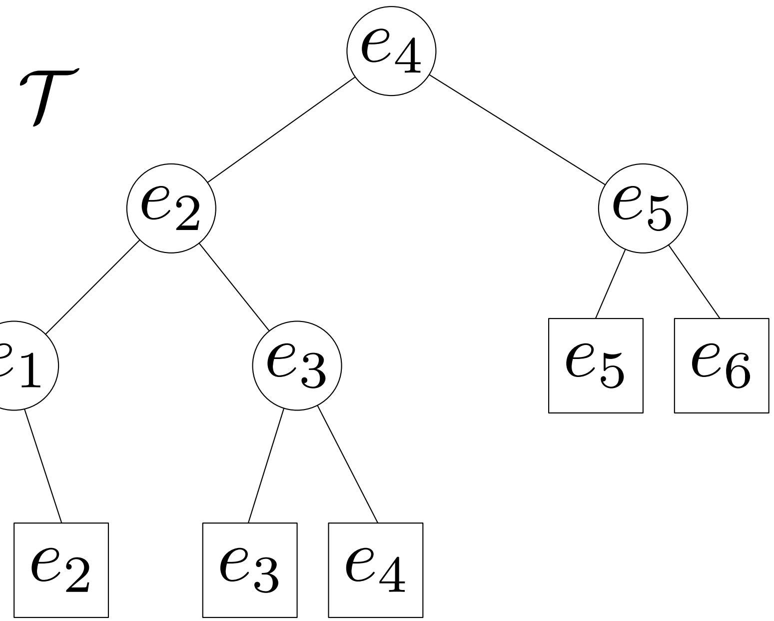
VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

$\mathcal{T} \leftarrow$ balancedBinaryTree(I)





Computing Visible Nodes

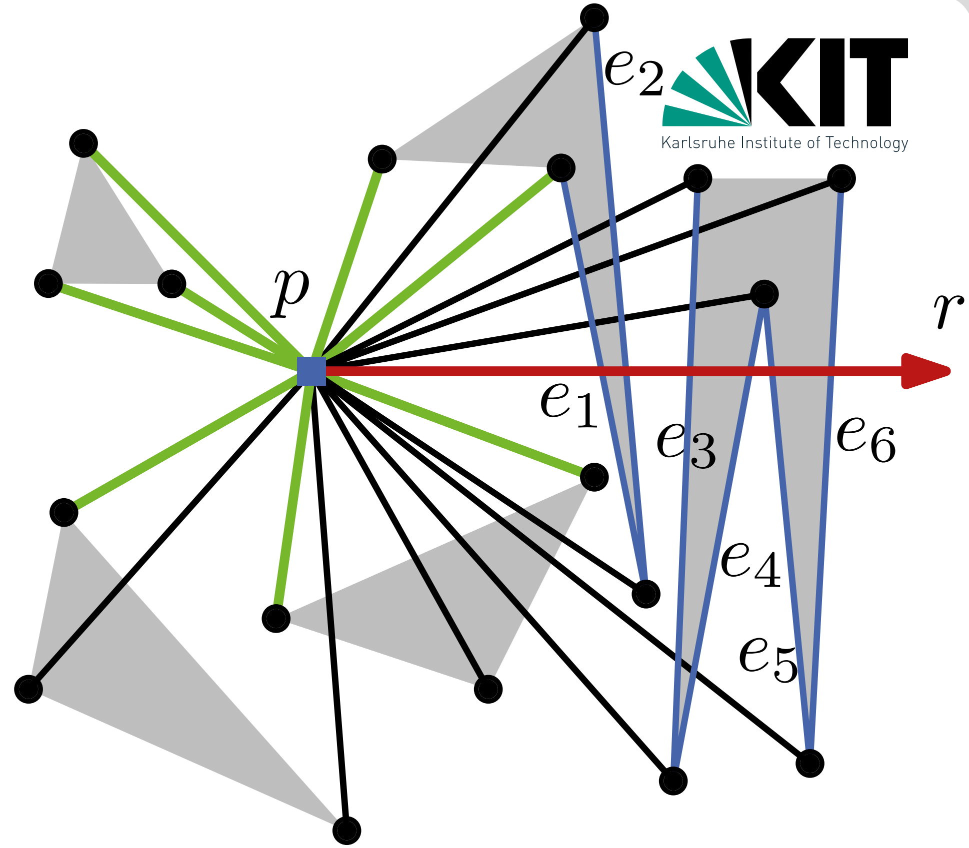
VisibleVertices(p, S)

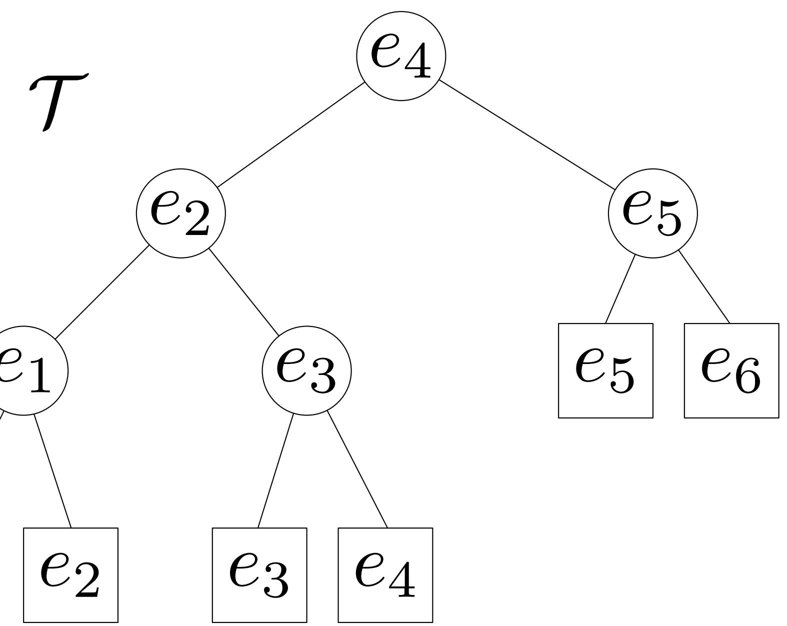
$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p





Computing Visible Nodes

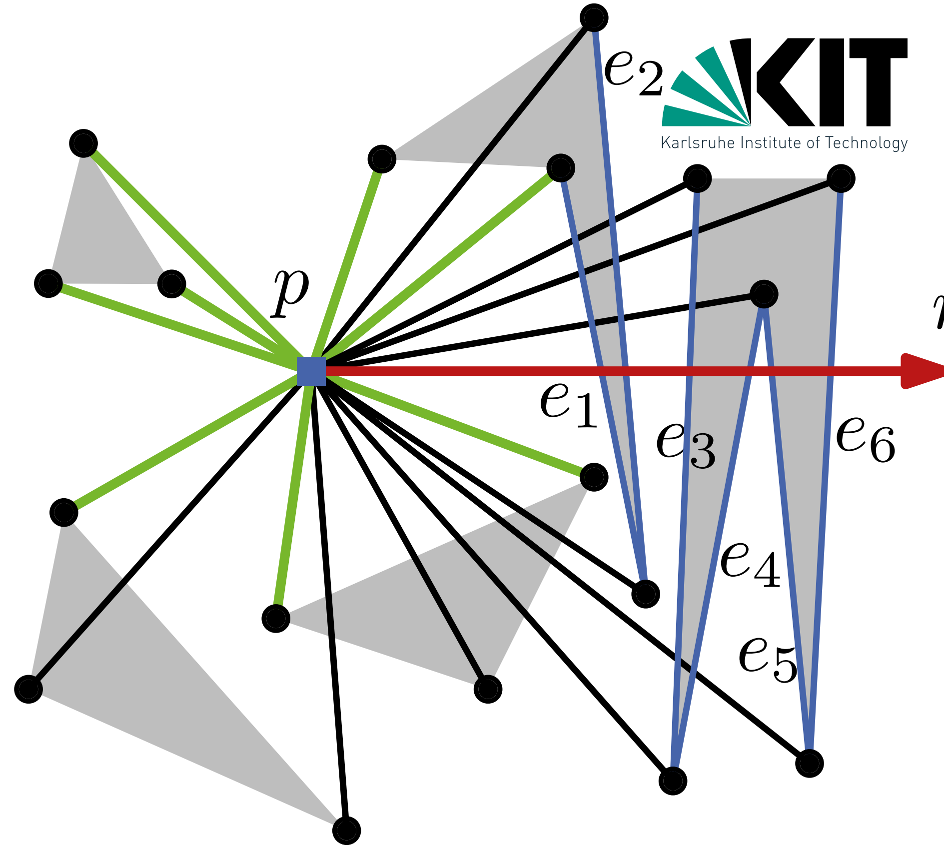
VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

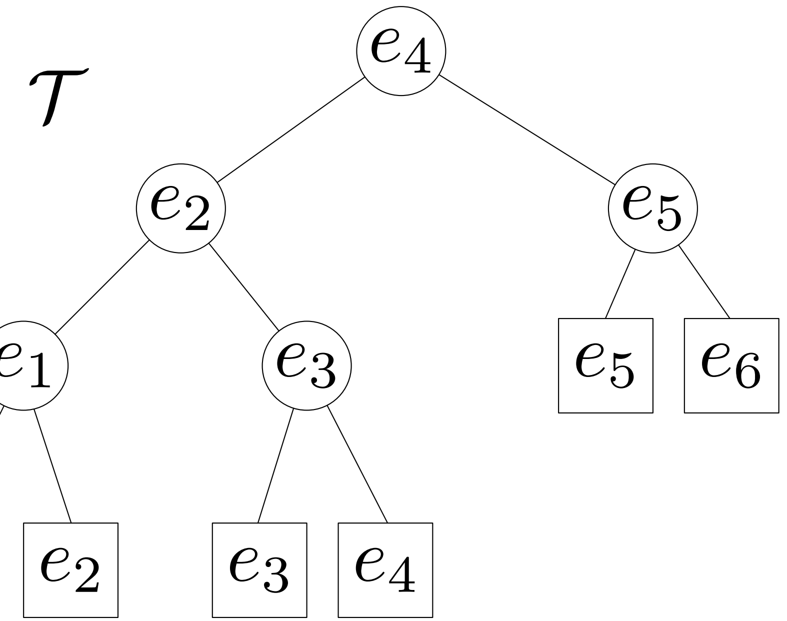
$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p



$v \prec v' :\Leftrightarrow$

$\angle v < \angle v'$ or
$(\angle v = \angle v'$ and $|pv| < |pv'|)$



Computing Visible Nodes

VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

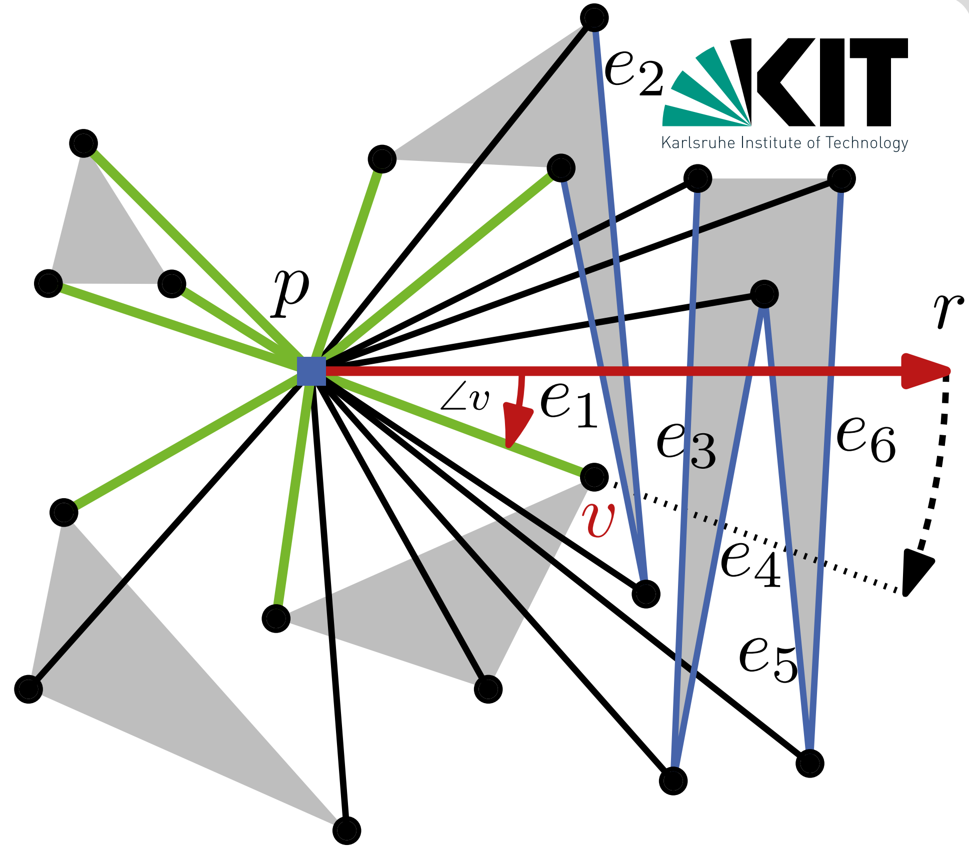
$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

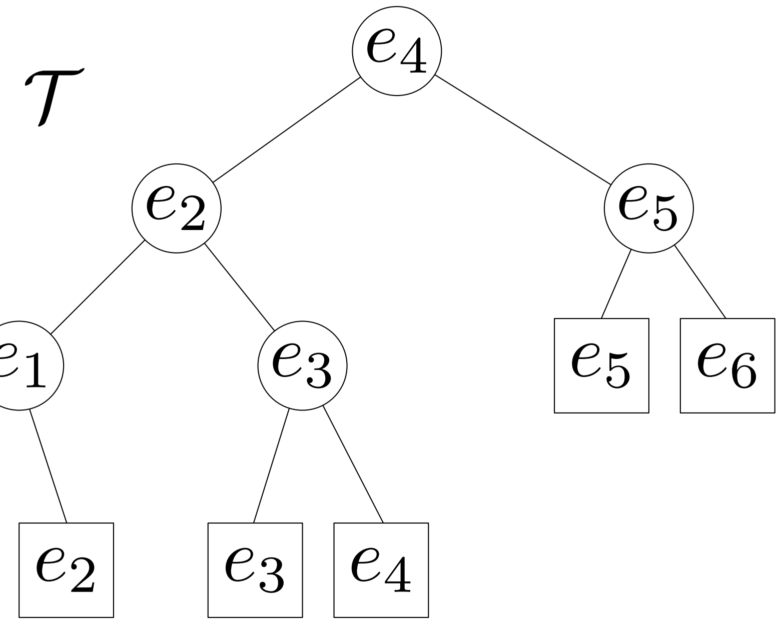
$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p

$v \prec v' :\Leftrightarrow$

$\angle v < \angle v'$ or
$(\angle v = \angle v'$ and $|pv| < |pv'|)$





Computing Visible Nodes

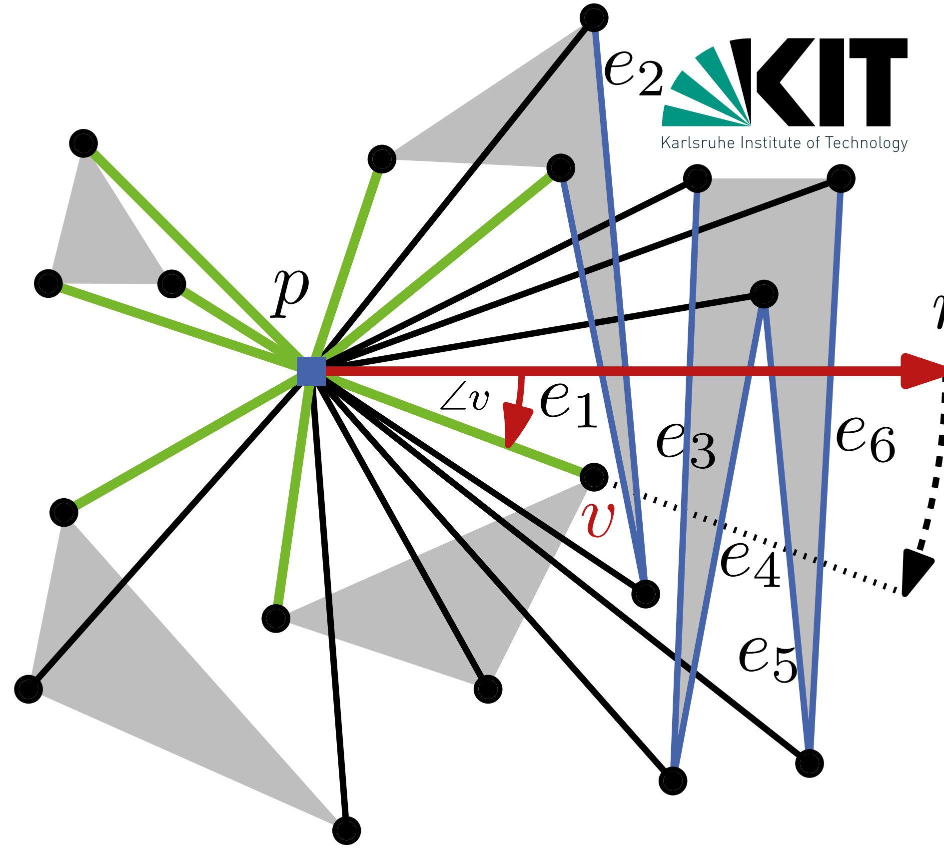
VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

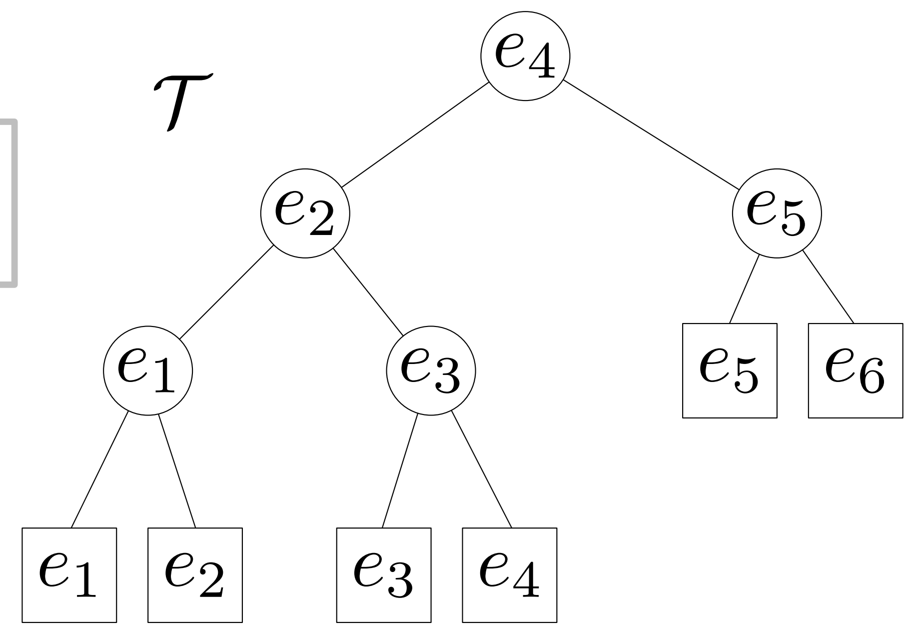
$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p



$v \prec v' :\Leftrightarrow$

$\angle v < \angle v'$ or
$(\angle v = \angle v'$ and $|pv| < |pv'|)$



Sweep method with rotation

Computing Visible Nodes

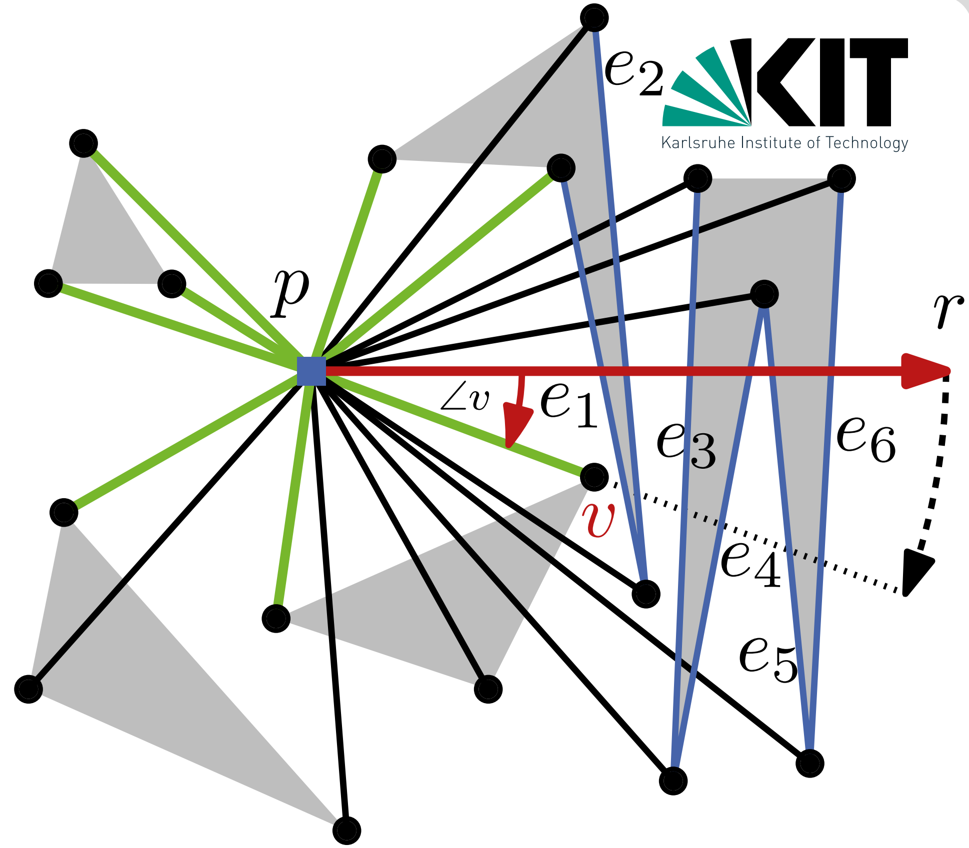
VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p



Computing Visible Nodes

VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p

$W \leftarrow \emptyset$

for $i = 1$ **to** n **do**

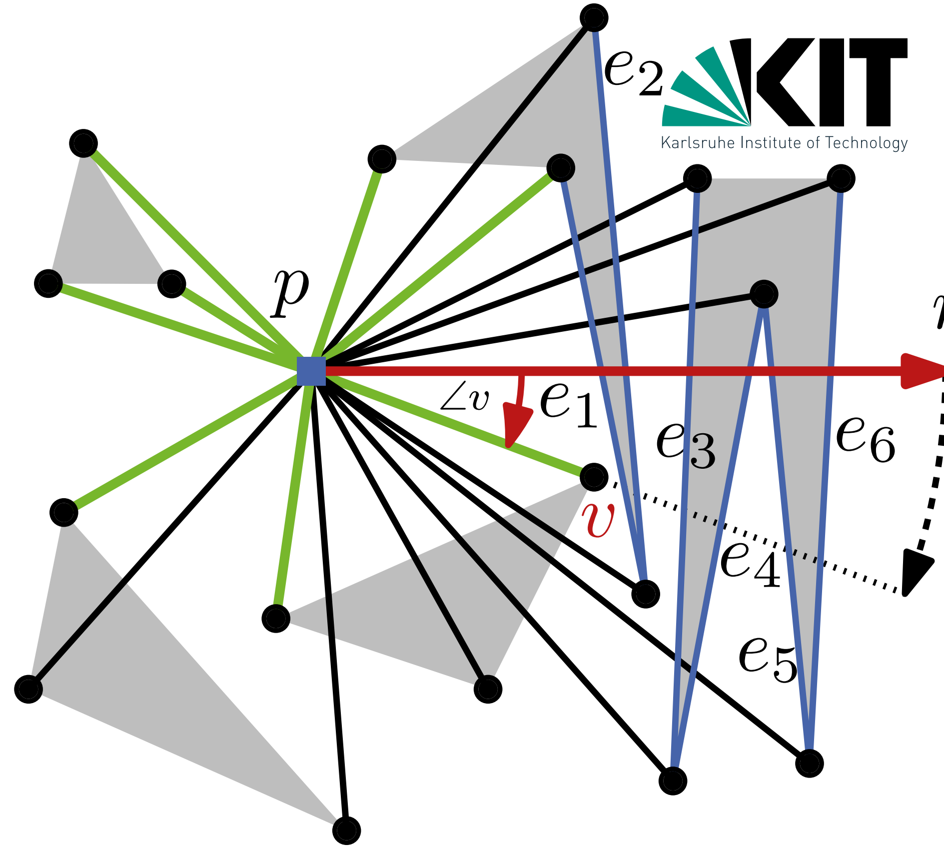
  if Visible(p, w_i) **then**

    $W \leftarrow W \cup \{w_i\}$

  Add to $\mathcal{T}$ edges incident to w_i: CW from $\overrightarrow{pw_i}^+$

  Remove from $\mathcal{T}$ edges incident to w_i:CCW from $\overrightarrow{pw_i}^-$

return W



Computing Visible Nodes

VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p

$W \leftarrow \emptyset$

for $i = 1$ **to** n **do**

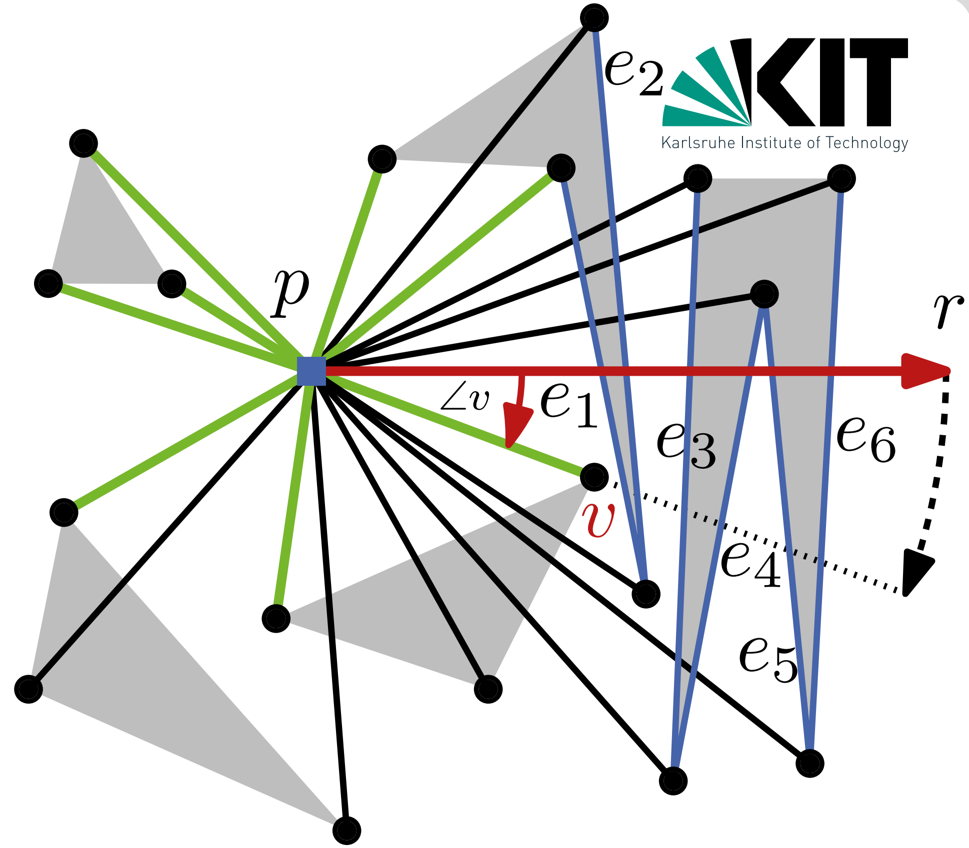
  if Visible(p, w_i) **then**

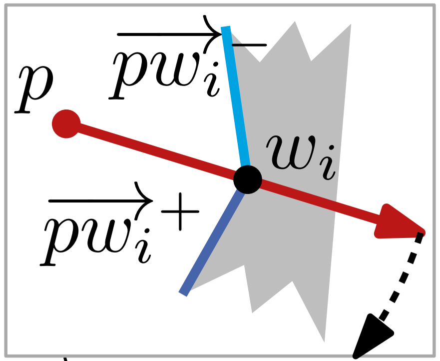
    $W \leftarrow W \cup \{w_i\}$

  Add to $\mathcal{T}$ edges incident to w_i: CW from $\overrightarrow{pw_i}^+$

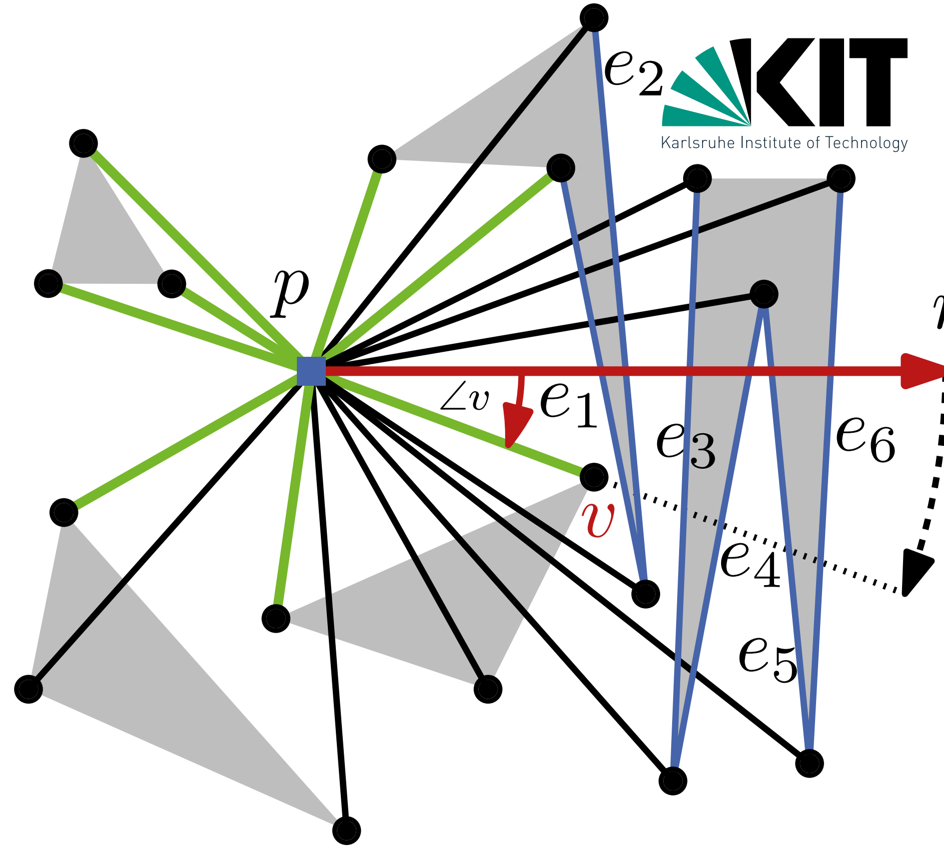
  Remove from $\mathcal{T}$ edges incident to w_i:CCW from $\overrightarrow{pw_i}^-$

return W





Computing Visible Nodes



VisibleVertices(p, S)

$r \leftarrow \{p + (k, 0) \mid k \in \mathbb{R}_0^+\}$

$I \leftarrow \{e \in E(S) \mid e \cap r \neq \emptyset\}$

$\mathcal{T} \leftarrow$ balancedBinaryTree(I)

$w_1, \ldots, w_n \leftarrow$ sort $V(S)$ in cyclic order around p

$W \leftarrow \emptyset$

for $i = 1$ **to** n **do**

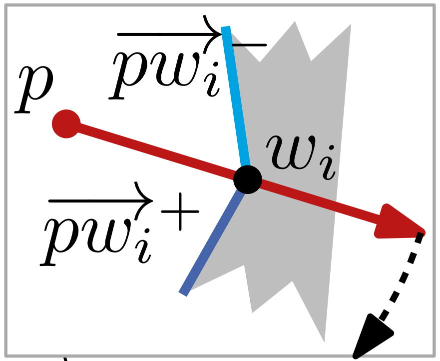
  if Visible(p, w_i) **then**

    $W \leftarrow W \cup \{w_i\}$

  Add to $\mathcal{T}$ edges incident to w_i: CW from $\overrightarrow{pw_i}^+$

  Remove from $\mathcal{T}$ edges incident to w_i:CCW from $\overrightarrow{pw_i}^-$

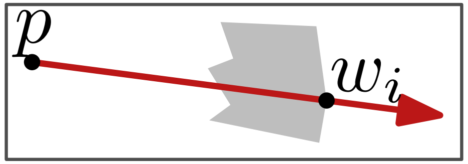
return W



Visibility Case Analysis

Visible(p, w_i)

if $\overline{pw_i}$ intersects polygon of w_i **then**
  return false



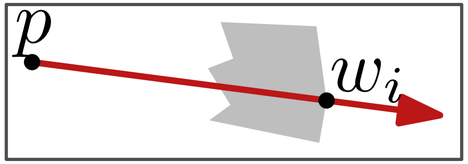
nil

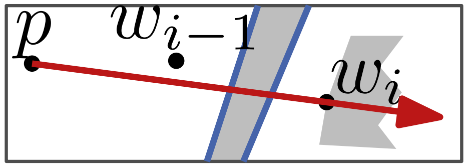
Visibility Case Analysis

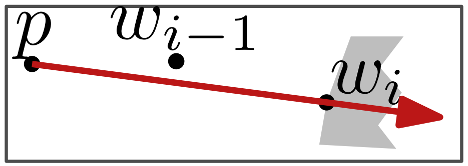
Visible(p, w_i)

if $\overline{pw_i}$ intersects polygon of w_i **then**
 return false

if $i = 1$ or $w_{i-1} \notin \overline{pw_i}$ **then**
 $e \leftarrow$ edge of leftmost leaf of $\mathcal{T}$
 if $e \neq$ nil and $\overline{pw_i} \cap e \neq \emptyset$ **then**
  return false
 else return true





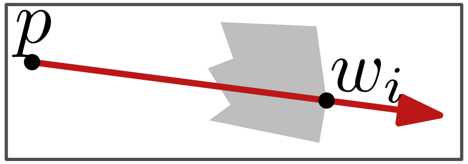


nil

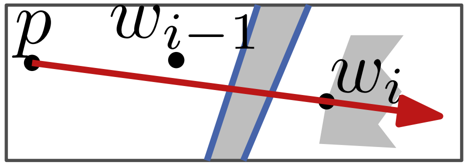
Visibility Case Analysis

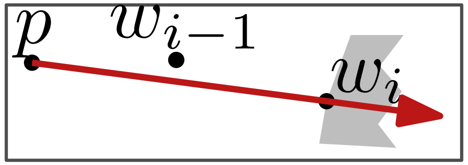
Visible(p, w_i)

if $\overline{pw_i}$ intersects polygon of w_i **then**
- **return** false

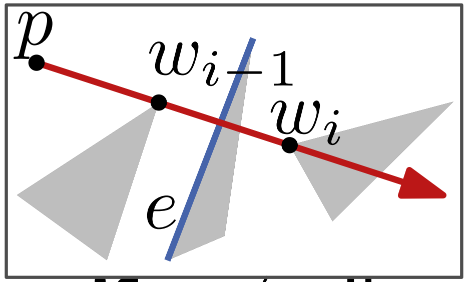


if $i = 1$ or $w_{i-1} \notin \overline{pw_i}$ **then**
- $e \leftarrow$ edge of leftmost leaf of $\mathcal{T}$
- **if** $e \neq$ nil and $\overline{pw_i} \cap e \neq \emptyset$ **then**
  - **return** false
- **else return** true





else
- **if** w_{i-1} is not visible **then**
  - **return** false
- **else**
  - $e \leftarrow$ find edge in $\mathcal{T}$, that $\overline{w_{i-1}w_i}$ cuts; **if** $e \neq$ nil
  - **then return** false
  - **else return** true



Summary

Thm 1: A shortest st-path in an area with polygonal obstacles with n edges can be computed in $O(n^2 \log n)$ time.

Summary

Thm 1: A shortest st-path in an area with polygonal obstacles with n edges can be computed in $O(n^2 \log n)$ time.

Proof:

- Correctness follows directly from Lemma 1.

Summary

Thm 1: A shortest st-path in an area with polygonal obstacles with n edges can be computed in $O(n^2 \log n)$ time.

Proof:

- Correctness follows directly from Lemma 1.
- Running time:
  – VisibleVertices takes $O(n \log n)$ time per vertex – n calls to VisibleVertices

Summary

Thm 1: A shortest st-path in an area with polygonal obstacles with n edges can be computed in $O(n^2 \log n)$ time.

Proof:

- Correctness follows directly from Lemma 1.
- Running time:
  – VisibleVertices takes $O(n \log n)$ time per vertex – n calls to VisibleVertices $\square$

$O(n^2)$ with duality
(see exercise or D. Mount [M12] Lect. 31)

Discussion

Robots are not single points...

Discussion

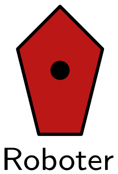
Robots are not single points...

For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles ($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).

Discussion

Robots are not single points...

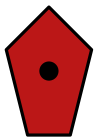
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

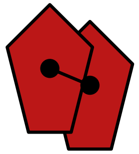
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

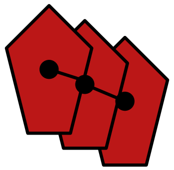
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

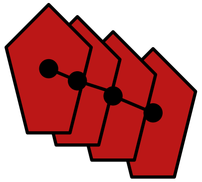
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

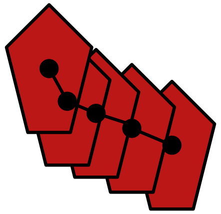
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

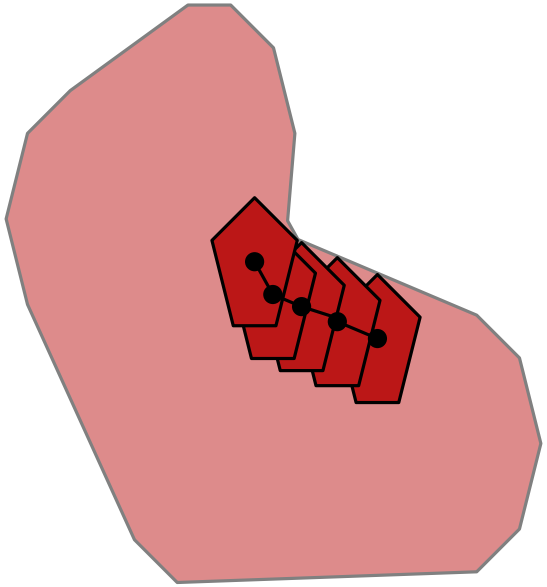
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

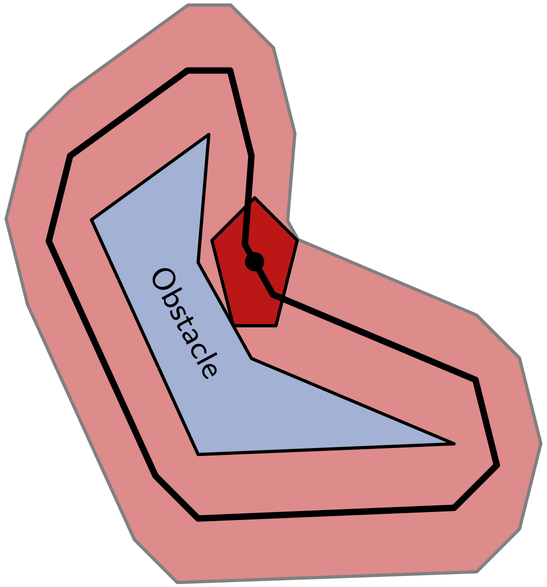
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
(→ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

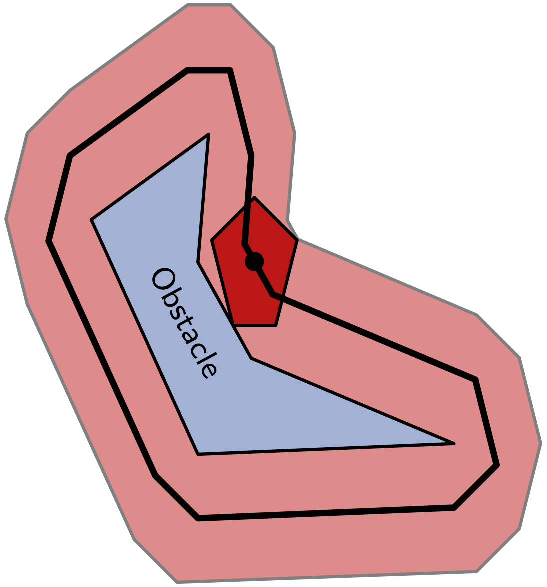
For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles
(→ Minkowski Sums, Ch. 13 in [BCKO08]).



Discussion

Robots are not single points...

For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles (→ Minkowski Sums, Ch. 13 in [BCKO08]).

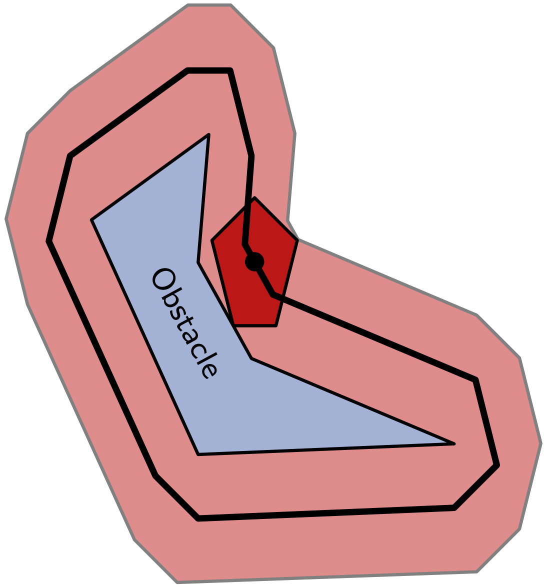


Can we compute faster than $O(n^2 \log n)$?

Discussion

Robots are not single points...

For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles ($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Can we compute faster than $O(n^2 \log n)$?

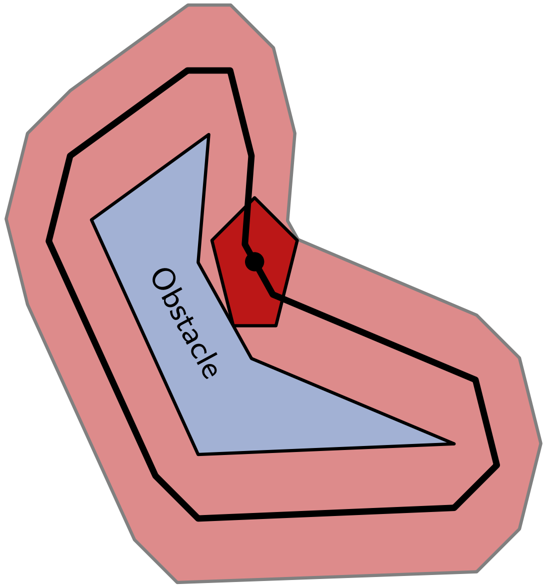
Yes, by use duality and a simultaneous rotation sweep for all points in the dual. Computing the arrangement, is also in $O(n^2)$. Even though G_{vis} can have $\Omega(n^2)$ edges, the visibility graph can be constructed even faster with an output sensitive $O(n \log n + m)$-time algorithm.

[Ghosh, Mount 1987]

Discussion

Robots are not single points...

For robots modelled by a convex polygon that cannot rotate, we can resize (grow) the polygons representing the obstacles ($\rightarrow$ Minkowski Sums, Ch. 13 in [BCKO08]).



Can we compute faster than $O(n^2 \log n)$?

Yes, by use duality and a simultaneous rotation sweep for all points in the dual. Computing the arrangement, is also in $O(n^2)$. Even though G_{vis} can have $\Omega(n^2)$ edges, the visibility graph can be constructed even faster with an output sensitive $O(n \log n + m)$-time algorithm.

[Ghosh, Mount 1987]

If you search only for *one* shortest Euclidean st-path, there is an algorithm with optimal $O(n \log n)$ time. [Hershberger, Suri 1999]