

# Shortest Path to a Segment and Quickest Visibility Queries

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## Abstract

We show how to preprocess a polygonal domain with a fixed starting point  $s$  in order to answer efficiently the following queries: Given a point  $q$ , how should one move from  $s$  in order to *see*  $q$  as soon as possible? This query resembles the well-known shortest-path-to-a-point query, except that the latter asks for the fastest way to *reach*  $q$ , instead of seeing it. Our solution methods include a data structure for a different generalization of shortest-path-to-a-point queries, which may be of independent interest: to report efficiently a shortest path from  $s$  to a query *segment* in the domain.

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## 1 Introduction

Finding shortest paths is a classical problem in computational geometry, and efficient algorithms are known for computing the paths both in simple polygons and polygonal domains with holes; see [33, 34] for surveys. In the *query version* of the problem one is given a fixed source point  $s$  in the domain, and the goal is to preprocess the domain so that the length of a shortest path from  $s$  to a query point  $q$  can be reported efficiently. The problem is solved by building the *shortest path map* (SPM) from  $s$  – the decomposition of the free space into cells such that for all points  $q$  within a cell the shortest  $s$ - $q$  path is combinatorially the same, i.e., traverses the same sequence of vertices of the domain.

The query in the shortest path problem can be stated as

Shortest path query: *Given a query point  $q$  lying in the free space, how should one move, starting from  $s$ , in order to **reach**  $q$  as soon as possible?*

Queries like this arise in surveillance and security, search and rescue, aid and delivery, and various other applications of the shortest path problem. In this paper we introduce and study a related problem that has a very similar query:

**Quickest visibility query (QVQ):** *Given a query point  $q$  lying in the free space, how should one move, starting from  $s$ , in order to **see**  $q$  as soon as possible?*



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Such a query may be natural in applications in which it is important to see (or become seen by) the query point – for inspection purposes, for coming within a shooting range, for establishing communication, etc. In contrast with shortest path queries, such quickest visibility queries have not been studied before, with the single exception of [28] where the problem was considered in simple polygons (in Section 5 we give improved results for this important special case).

The other variant of the shortest path query problem, which we consider in this paper, deals with *segments* instead of points as query objects:

**Shortest path to a segment query (SPSQ):** *Given a query segment  $ab$  lying in the free space, how should one move, starting from  $s$ , in order to reach  $ab$  as soon as possible?*

To our knowledge such queries have not been studied before. We show that in nearly-quadratic time a nearly-quadratic-size data structure can be built to answer SPSQ in polylogarithmic time (logarithmic-time query can be achieved with nearly-cubic preprocessing time and space). We apply SPSQ as a subroutine in an algorithm for QVQ: given the query point  $q$  in an instance of QVQ, build the visibility polygon of  $q$  and use SPSQ for each “window” (edge running through the free space) of the polygon to choose the best window through which  $q$  can be seen.

## 1.1 Notation

Let  $D$  denote the given polygonal domain; let  $n, h$  be the number of vertices and holes of  $D$ , respectively. Assume that no two vertices of  $D$  have the same  $x$ - or  $y$ -coordinate. Two points  $p, q \in D$  see each other if the segment  $pq$  fully belongs to the domain (we consider  $D$  as a closed set, so that  $pq$  may go through a vertex of  $D$  or otherwise overlap with the boundary of the domain). Let  $E$  be the size of the *visibility graph* of  $D$  – the graph on vertices of  $D$  with edges between pairs of mutually visible vertices (i.e., pairs of vertices that can be connected with a single link). We also introduce an additional definition related to “3-link visibility” between vertices of  $D$ : let  $\Pi$  be the number of pairs of vertices that can be connected by a right-turning 3-link path that makes  $90^\circ$  turns at both of its bends (refer to Fig. 3).

Let  $P, S, Q$  denote the preprocessing time, size of the built data structure and query time, respectively, for an algorithm for answering quickest visibility queries (QVQ) in  $D$ . The query point will be generally denoted by  $q$ . Let  $V(q)$  denote the *visibility polygon* of  $q$  (the set of points seen by  $q$ ); let  $K$  denote the complexity (the number of sides) of  $V(q)$ . We use  $P_v, S_v, Q_v$  to denote the preprocessing time, size of the structure and query time for an algorithm for the problem of building  $V(q)$ . Finally, we denote by  $P_s, S_s, Q_s$  the corresponding parameters of an algorithm for SPSQ – the problem of reporting length of the shortest path to a query segment lying in  $D$ .

Slightly abusing the terminology, we will not differentiate between the two variants of path queries: reporting the *length* of the optimal path and outputting the path itself; similarly to other path query problems, the latter can usually be done straightforwardly (by following back pointers) in additional time proportional to the combinatorial complexity of the path.

## 1.2 Related work

A shortest path between two points in a simple polygon ( $h = 0$ ) can be found in linear time [7, 30]. The query version (i.e., building the SPM) can be solved within the same time [19];

using the SPM, the length of the (unique) shortest path to a query point can be reported in time  $O(\log n)$ .

For polygons with holes the *continuous Dijkstra* paradigm [32] leads to an  $O(n \log n)$  time algorithm [25] for building the SPM, by propagating a *wave* (which we call the *p-wave*) from  $s$  through the free space at unit speed, so that the points reached by the wavefront at any time  $\tau$  are exactly the points at geodesic distance  $\tau$  from  $s$  (see, e.g., Fig. 4 where gray shows the area covered by the p-wave, and Fig. 6 (left), where the p-wave is blue). At any time during the propagation, the wavefront consists of a sequence of *wavelets* – circular arcs centered on vertices of  $D$ , called *generators* of the wavelets; the radius of each arc grows at unit speed. Boundaries between adjacent wavelets trace edges of the SPM (the edges are called *bisectors*, and are further classified in [13] as “walls” and “windows”<sup>1</sup> depending on whether there exist two homotopically distinct shortest paths to points on the bisector); this way the algorithm also builds the SPM which allows one to answer the shortest path queries in  $O(\log n)$  time per query. Vertices of the SPM are vertices of  $D$  and *triple points*, at which three edges of the map meet (w.l.o.g. four edges of SPM never meet at the same point); the overall complexity of the SPM is linear [25]. Using the continuous Dijkstra method, the quickest way to see a point and the shortest path to a segment (i.e., solutions to single-shot, non-query versions of QVQ and SPSQ) can be found in  $O(n \log n)$  time by simply declaring  $V(q)$  and the segment as obstacles and waiting until the p-wave hits them.

Computing visibility from a point was first studied in simple polygons, for which an  $O(n)$ -time solution was given already in 1987 [27]. For polygons with holes an optimal,  $O(n+h \log h)$ -time algorithm was presented by Heffernan and Mitchell [23]. The query version of the problem has been well studied too: For simple polygons Guibas, Motwani and Raghavan [20] and Bose, Lubiw and Munro [3] gave algorithms with  $P_v = O(n^3 \log n)$ ,  $S_v = O(n^3)$  and  $Q_v = O(\log n + K)$ ; Aronov, Guibas, Teichman and Zhang [2] achieve  $P_v = O(n^2 \log n)$ ,  $S_v = O(n^2)$  and  $Q_v = O(\log^2 n + K)$ . For polygons with holes Zarei and Ghodsi [42] achieve  $P_v = O(n^3 \log n)$ ,  $S_v = O(n^3)$ ,  $Q_v = O(K + \min(h, K) \log n)$ ; Inkulu and Kapoor [26] combine and extend the approaches from [42] and [2] presenting algorithms with several tradeoffs between  $P_v$ ,  $S_v$  and  $Q_v$ , in particular, with  $P_v = O(n^2 \log n)$ ,  $S_v = O(n^2)$ ,  $Q_v = O(K \log^2 n)$  (see also [9], as well as [31] giving  $P_v = O(n^2 \log n)$ ,  $S_v = O(n^2)$ ,  $Q_v = O(K + \log^2 n + h \log(n/h))$ ). A recent paper by Bunqui et al. [4] reports on practical implementation of visibility computation in an upcoming CGAL [6] package.

More generally, both visibility and shortest paths computations are textbook subjects in computational geometry – see, e.g., the respective chapters in the handbook [17] and the books [38, 15]. Visibility meets path planning in a variety of geometric computing tasks. Historically, the first approach to finding shortest paths was based on searching the visibility graph of the domain. Visibility is vital also in computing *minimum-link* paths, i.e., paths with fewest edges [37, 41, 36]. Last but not least, “visibility-driven” route planning is the subject in *watchman route* problems [5, 12, 35, 39, 11] where the goal is to find the shortest path (or a closed loop) from which every point of the domain is seen. Apart from the above-mentioned theoretical considerations, visibility and motion planning are closely coupled in practice: computer vision and robot navigation go hand-in-hand in many courses and real-world applications.

Reporting optimal paths to *non-point* query objects has not received much attention; we

<sup>1</sup> We admit that the term “window” is overused, since it also denotes edges of the visibility polygon  $V(q)$ . Still, our two different usages of the term are well separated in the text, and are always apparent from the context.

are aware of work only for simple polygons. For efficient (logarithmic-time) queries between two convex polygons within a simple polygon, preprocessing can be done in linear time for Euclidean distances [10] and cubic time (and space) for link distance [1, 10].

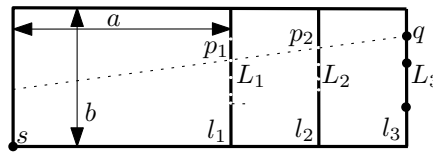
On the specific problem of quickest visibility queries addressed in this paper, Khosravi and Ghodsi [28] considered QVQs in *simple* polygons. They gave an algorithm for quickest visibility with logarithmic-time queries after quadratic-time preprocessing for building a quadratic-size structure:  $P = O(n^2)$ ,  $S = O(n^2)$ ,  $Q = O(\log n)$ . We improve the preprocessing and storage to linear, achieving  $P = O(n)$ ,  $S = O(n)$ ,  $Q = O(\log n)$  for simple polygons (Section 5).

### 1.3 Overview of the results

- We start by giving a conditional lower bound connecting  $P$  and  $Q$ : Section 2 shows that 3SUM on  $n$  numbers can be solved in time  $O(P + nQ)$ . For instance subquadratic preprocessing time ( $P = o(n^2)$ ) and sublinear query time ( $Q = o(n)$ ) would lead to a subquadratic-time algorithm for 3SUM (see [18] for a recent major breakthrough on the 3SUM problem). The lower bound provides us with some justification for not obtaining sub-quadratic preprocessing time  $P$  for the QVQ. (Also more broadly, solutions to visibility and/or closely related link-distance query problems often use cubic-time preprocessing [42, 1, 10].)
- Section 3 employs the following natural approach to quickest visibility query.
  - (1) Build the visibility polygon  $V(q)$  of the query point  $q$ ;  $V(q)$  is a star-shaped polygon any side of which is either a piece of a boundary edge of  $D$ , or is a *window* – extension of the segment  $qv$  for some vertex  $v$  of  $D$ .
  - (2) For each window find the shortest path from  $s$  to the window, and choose the best window to go to.

The approach leads to an algorithm for QVQ with  $P = P_v + P_s$ ,  $S = S_v + S_s$ ,  $Q = Q_v + KQ_s$  (refer to Section 1.1 for the notation). Problem (1) – building  $V(q)$  – has been well studied (refer to Section 1.2 for the known bounds on  $P_v$ ,  $S_v$  and  $Q_v$ ). On the contrary, problem (2) – building a shortest path map for *segments* – has not been studied before. In Section 3.2 we give the first results for shortest path to a segment query (which we abbreviated SPSQ above) achieving  $P_s = O(n^3 \log n)$ ,  $S_s = O(n^3 \log n)$ ,  $Q_s = O(\log n)$ . Our solution is based on first designing a data structure for *horizontal* segments (Section 3.1) with  $P_s = O(n \log n)$ ,  $S_s = O(n \log n)$ ,  $Q_s = O(\log n)$  – a result which may be interesting in its own right. The data structure for SPSQ for arbitrary segments is then built straightforwardly since there are  $O(n^2)$  combinatorially different orientations: the data structure for arbitrarily oriented segments is thus just an  $O(n^2)$ -fold replication of the structure for horizontal ones (we also give bounds in terms of sizes,  $E$  and  $\Pi$ , of visibility structures in  $D$ ). Alternatively, in Section 3.3 we give an algorithm with  $P_s = O(n^2 \log n)$ ,  $S_s = O(n^2 \log n)$ ,  $Q_s = O(\log^2 n)$  based on storing “snapshots” of the p-wave propagation in the continuous Dijkstra.

- In Section 4 we introduce the full *Quickest Visibility Map* (QVM) – the decomposition of  $D$  into cells such that within each cell the quickest visibility query has combinatorially the same answer: the shortest path to see any point within a cell goes through the same sequence of vertices of  $D$ . Our algorithm for building the map has  $P = O(n^8 \log n)$ ,  $S = O(n^7)$ ,  $Q = O(\log n)$ . We also observe that the QVM has  $\Omega(n^4)$  complexity.
- In Section 5 we consider the case when  $D$  is a simple polygon. We give linear-size data structures that can be constructed in linear time, for answering QVQs and SPSQs



■ **Figure 1**  $D$  is long:  $a \gg b$ . The ray  $qp_2$  (dotted) can reach all the way to the left, provided there exists a gap ( $p_1$ ) on  $l_1$  collinear with  $q$  and  $p_2$ .

in logarithmic time:  $P = O(n)$ ,  $S = O(n)$ ,  $Q = O(\log n)$ ,  $P_s = O(n)$ ,  $S_s = O(n)$ ,  $Q_s = O(\log n)$ .<sup>2</sup>

We invite the reader to play with our applet demonstrating QVM at <http://www.cs.helsinki.fi/group/compgeom/qvm/>.

## 2 A lower bound

In the *3SUM* problem the input is a set of numbers and the goal is to determine whether there are three numbers whose sum is 0. We connect  $P$  and  $Q$  (see Section 1.1 for the notation) with the *3SUM* problem.

► **Theorem 1.** *A 3SUM instance of size  $n$  can be solved in  $O(P + nQ)$  time.*

**Proof.** We use a construction similar to the one in the proof of *3SUM*-hardness of finding minimum-link paths [36]. Start from an instance of the *GeomBase* problem: Given a set  $S = L_1 \cup L_2 \cup L_3$  of  $n$  points lying on 3 vertical lines  $l_1, l_2, l_3$  respectively, do there exist collinear points  $p_1 \in L_1, p_2 \in L_2, p_3 \in L_3$ ? It was shown in [14] that solving *GeomBase* is as hard as solving *3SUM* with  $n$  numbers. Construct the domain  $D$  for quickest visibility queries as follows (Fig. 1): The lines  $l_1, l_2, l_3$  are obstacles; turn each point from  $L_1 \cup L_2$  into a gap punched in the obstacle. Squish vertically the whole construction, i.e., make the distances between the lines much larger than the vertical extent of  $S$ ; this way all the rays  $p_2p_1$  with  $p_2 \in L_2, p_1 \in L_1$  are confined to a narrow beam. Put the whole construction in a long box so that the beam shines onto its left side. Put  $s$  in the lower left corner of the box.

Now do quickest visibility queries to points in  $L_3$ . If some point  $q \in L_3$  is collinear with some points  $p_1 \in L_1, p_2 \in L_2$ , then  $q$  can be seen by traveling at most  $b$  from  $s$ ; otherwise, one needs to travel at least  $a$  to  $L_1$ . Thus by making at most  $n$  queries we can solve the *GeomBase*. ◀

The above proof can be extended in several ways. E.g., since  $a$  can be arbitrarily large in comparison with  $b$ , even approximate answers to queries would solve the *3SUM* problem.

## 3 Querying shortest paths to windows

The quickest way to see the query point  $q$  from  $s$  is the quickest way to reach (the boundary of)  $V(q)$ , or equivalently, to reach a window of  $V(q)$ . Assuming the visibility polygon of  $q$  had been built by existing methods (see Section 1.2), answering QVQ boils down to determining the window closest to  $s$ . We do not have a better way of accomplishing this than to do shortest path queries to each window in succession, which leads to the problem of building

<sup>2</sup> Some results from this section were reported in EuroCG [29].

a data structure to answer efficiently shortest-path-to-a-segment query (abbreviated SPSQ above) – the subject of this section.<sup>3</sup>

### 3.1 Horizontal segments

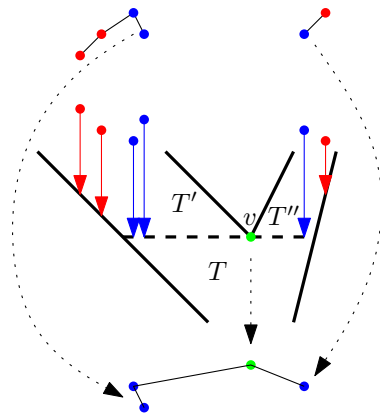
In this subsection we present a data structure for SPSQ for fixed-orientation (w.l.o.g. horizontal) segments; in the next subsection we extend the structure to handle arbitrary segments (and in Section 3.3 we present a structure for arbitrary segments, based on different techniques). The shortest path to a segment  $ab$  touches it at  $a$ , at  $b$ , or in the interior; we will focus on shortest paths to the interior, since shortest paths to  $a$  or  $b$  are answered with the SPM. Such a path follows the shortest path to some vertex  $v$  of  $D$  and then uses the perpendicular from  $v$  onto  $ab$ ; i.e., the last link of the path is vertical. We describe our data structure only for the case of paths arriving at  $ab$  from above, for which this last link is going *down*; an analogous structure is built for the paths arriving to the query from below.

The data structure is the horizontal trapezoidation of  $D$  augmented with some extra information for each trapezoid  $T$ ; specifically – the set of vertices that see the trapezoid from above (i.e., vertices from which downward rays intersect  $T$ ). Of course, the information is not stored explicitly with each trapezoid (for this may require  $\Omega(n)$  information in each of  $\Omega(n)$  trapezoids); instead, the information is stored in persistent balanced binary trees. The vertices in the trees are sorted by  $x$ -coordinate. To enable  $O(\log n)$ -time range minimum queries, each internal node stores the minimum of  $d(v) + v_y$  values over all vertices  $v$  in the subtree of the node, where  $d(v)$  is the geodesic distance from  $s$  to  $v$  (which can be read from the SPM) and  $v_y$  is the  $y$ -coordinate of  $v$ . Knowing the minimum of these values over the range of a segment is our ultimate goal, because the length of the shortest path that arrives to the segment at ordinate  $y$  with last link dropped from  $v$  is  $d(v) + v_y - y$ .

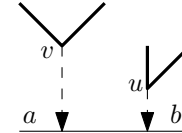
We build the trees as follows. Let  $\prec$  be the “aboveness” relation on the trapezoids (i.e.,  $T \prec T'$  iff  $T'$  is incident to  $T$  from above). We traverse the trapezoids using a topological order of the DAG for  $\prec$  (e.g., in the order of the  $y$ -coordinates of trapezoid top sides) and compute the trees for the trapezoids as follows (Fig. 2): If a trapezoid  $T$  does not have a successor in  $\prec$ , then  $T$  is a triangle (due to the non-degeneracy assumption on  $D$ ), and the tree  $\tau(T)$  for  $T$  simply stores the top vertex of  $T$  if the downward ray from the vertex goes inside  $T$ ; if the ray does not enter  $T$  (i.e.,  $T$  has an obtuse angle at the base), then  $\tau(T)$  is empty. If  $T$  has successors, then for each trapezoid  $T'$  that succeeds  $T$  in  $\prec$ , we take a persistent copy of the tree  $\tau(T')$  and remove from it all vertices that do not see the boundary  $T \cap T'$  between the trapezoids (the removal is a split operation on the copy). After the removal has been done for all successors of  $T$ , we merge the copies of the trees into the tree  $\tau(T)$ . Additionally, if  $T$  has a vertex of  $D$  on its top edge, then the vertex is added to  $\tau(T)$ .

To answer SPSQ, find the trapezoid  $T$  containing the query segment  $ab$  (recall our assumption that  $ab$  lies in the free space, and hence – in a single trapezoid) and choose the right history snapshot. Then perform the range minimum query  $[a, b]$  to obtain the vertex  $v \in \tau(T)$  of  $D$  with the smallest  $d(v) + v_y$  (since  $v \in \tau(T)$ , the vertex sees  $ab$  when looking down and  $a \leq v_x \leq b, v_y \geq y$ ); this will be the vertex from which the interior of the segment is reached in the quickest way. The shortest path via  $v$  is compared with the

<sup>3</sup> We do not know how to take advantage of the fact that windows are quite special – maximal free-space segments anchored at vertices of  $D$ . On one hand this makes our solution more general, as it applies to arbitrary segments; on the other hand, it leaves open the possibility of designing a more efficient algorithm tailored to the special case of windows.



■ **Figure 2** Trees for the trapezoids. Red vertices are removed from persistent copies of  $\tau(T')$  and  $\tau(T'')$ ; the other vertices (blue) remain in the copies. Then the copies are merged to form  $\tau(T)$ . Finally,  $v$  is added to  $\tau(T)$ .



■ **Figure 3**  $u$  and  $v$  can be connected by a 3-link path making only right turns.  $ab$  is seen by  $u$  and  $v$ , and  $d(u) + u_y = d(v) + v_y$ .

shortest paths to  $a$  and  $b$ , altogether in  $O(\log n)$  query time. Thus our data structure provides  $P_s = O(n \log n)$ ,  $S_s = O(n \log n)$ ,  $Q_s = O(\log n)$  for horizontal segments.

### 3.2 Arbitrary segments

To support all directions of query segments, we build our structure from previous subsection for all rotations of  $D$  at which the data structure changes. The data structure changes at three types of events: (1) when two visible vertices get the same  $x$ -coordinates, (2) when two visible vertices get the same  $y$ -coordinates, and (3) when some query segment can be reached equally fast from two vertices, i.e., when the two vertices get the same  $d(v) + v_y$  values (Fig. 3). The number of the first two events is bounded by the size  $E$  of the visibility graph of  $D$ , and the number of the third-type events is bounded by the number  $\Pi$  of pairs of vertices that can be connected by a right-turning 3-link path that turns by 90 degrees at its both bends. Thus we need to replicate our data structure only  $O(E + \Pi)$  times (which may be much smaller than the naive upper bound of  $O(n^2)$ ).

To find the rotation angles for the first two types of events, we precompute the visibility graph of  $D$  (takes  $O(E + n \log n)$  time [16]). We can discover the third-type events “on-the-fly”, while actually rotating the domain. For that we make our trees “kinetic” by assigning to each internal node  $u$  of the trees the “expiration time” (rotation angle) when the vertex with lowest value of  $d(v) + v_y$  in the subtree of  $u$  changes; the time for  $u$  can be computed when  $u$  is constructed, using the lowest  $d(v) + v_y$  values in the subtrees of children of  $u$ . Computing the expiration time is done once per node instance of the trees.

Overall we obtain  $P_s = O((E + \Pi)n \log n)$ ,  $S_s = O((E + \Pi)n \log n)$ ,  $Q_s = O(\log n)$ .

► **Remark.** We could reuse the information between the rotations and get a persistent data structure with  $P_s = O(n^2 \log^3 n)$ ,  $S_s = O(n^2 \log^3 n)$ ,  $Q_s = O(\log^2 n)$ , but this is inferior to the performance of our data structure in the next section. Potentially one could also get a persistent data structure with  $P_s = Q_s = O((E + \Pi)\text{polylog } n)$ ,  $Q_s = O(\text{polylog } n)$ ; we, however, were not able to do this.

### 3.3 Continuous Dijkstra-based algorithm

We now give another data structure for SPSQ, based on storing “snapshots” of p-wave propagation (recall that p-wave is the wave propagated during the continuous Dijkstra algorithm for building the SPM). Recall (Section 1.2) that vertices of the SPM are vertices of  $D$  and triple points (at which three edges of the map meet). We say that time  $t_i$  is *critical* if the distance from  $s$  to a vertex of SPM is equal to  $t_i$ ; since SPM has linear complexity, there are  $O(n)$  critical times. For each critical time  $t_i$  we store the *geodesic disk*  $D_i$  of radius  $t_i$ , i.e., the set of points in  $D$  whose geodesic distance to  $s$  is at most  $t_i$ ; the disk is an  $O(n)$ -complexity region bounded by circular arcs (wavelets) and straight-line segments (obstacle edges). We construct data structures for two types of queries: “Given a segment  $ab$ , lying in the free space, does it intersect  $D_i$ ?” and “Given a segment  $ab$  lying outside  $D_i$ , where will the segment hit the disk if dragged perpendicularly to itself?”.

#### 3.3.1 Determining $i$

Assume that  $D_i$  has been preprocessed for point location, to test in  $O(\log n)$  time whether  $a$  or  $b$  is inside  $D_i$  (in which case, obviously  $ab$  intersects  $D_i$ ). To answer the intersection query when neither  $a$  nor  $b$  lies inside  $D_i$ , we look at the complement,  $C_i$ , of  $D_i$  in  $D$ ; obviously, a segment intersects the nonobstacle boundary of  $D_i$  iff it intersects the (nonobstacle) boundary of  $C_i$ . The set  $C_i$  may have several connected components (Fig. 4), at most one of which surrounds  $D_i$ . Each connected component  $C$  of  $C_i$  is preprocessed separately as follows: Let  $\mathcal{H}$  be the set of holes lying inside  $C$ . Let  $\hat{C} = C \cup_{H \in \mathcal{H}} H$  be  $C$  together with the holes  $\mathcal{H}$ ; the set  $\hat{C}$  either has no holes (i.e., is simply connected) or has one hole ( $D_i$ , if  $C$  is the component that surrounds  $D_i$ ). In any case  $\hat{C}$  can be preprocessed in  $O(|C| \log n)$  time to answer ray shooting queries in  $O(\log n)$  time [8], where  $|C|$  is the complexity of  $C$  (the geodesic triangulations framework of [8] extends to regions with circular arcs on the boundary). To answer the intersection query we first determine the connected component  $C_a$  of  $C_i$  that contains  $a$  (assume that all connected components have been preprocessed for point location) and use the ray shooting data structure on  $\hat{C}_a$  to determine where the ray  $r$  from  $a$  through  $b$  exits  $\hat{C}_a$ ;  $ab$  intersects  $D_i$  iff  $r$  exits into  $D_i$  and does so before  $b$ . Note that here we crucially use the assumption that the query segment lies in the free space: we do not care if  $r$  intersects holes on the way to  $D_i$  (extending our algorithm to handle segments that may intersect holes is an open problem).

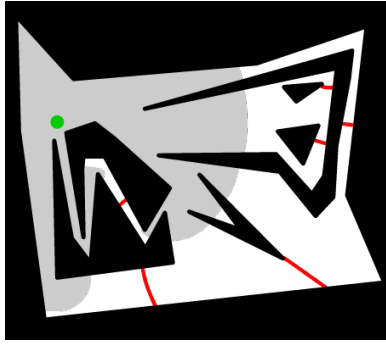
With the above data structures built for all disks  $D_i$ , we can do binary search on the critical times to determine the index  $i$  such that the query segment  $ab$  intersects  $D_{i+1}$  but does not intersect  $D_i$ , which means that  $ab$  is reached by the wavefront at some time between  $t_i$  and  $t_{i+1}$ . We spend  $O(\log n)$  for ray shooting per choice of  $i$ , yielding  $O(\log^2 n)$  time overall to determine  $i$ . Now the goal is to determine which wavelet of  $D_i$  hit  $ab$  first.

#### 3.3.2 Determining the wavelet

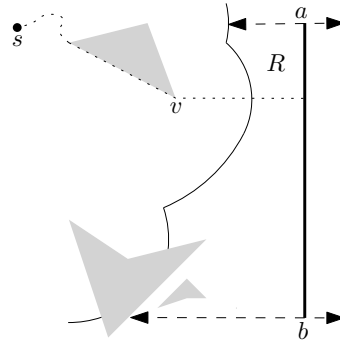
Using the point location data structure on  $C_i$  we find the component  $C$  of  $C_i$  that contains  $ab$  (the segment must fully lie inside a single connected component, for otherwise it intersects  $D_i$ ). Next, using the ray shooting data structure on  $C$ , we shoot rays within  $C$ , with sources at  $a$  and at  $b$ , firing orthogonal to  $ab$ , in both directions. This yields one region on each side of  $ab$ , and we consider the two regions separately; let  $R$  be the region on one of the sides (Fig. 5).

The boundary of  $R$  consists of  $ab$ , a ray shot from  $a$  to the boundary of  $C$ , a portion of the (outer) boundary of  $C$  (which may include circular-arc wavelets alternating with sequences





■ **Figure 4**  $s$  is green,  $D_i$  is gray, and  $C_i$  (the part of free space not reached by the wave) is white; it has four connected components, one of which has two holes inside it. Red curves are the walls (bisectors with more than one homotopy type of the shortest path) of the SPM.



■ **Figure 5**  $D_i$  is bounded by circular-arc wavelets (solid curves) and edges of obstacles (gray); the rays orthogonal to  $ab$  are dashed. The shortest path to  $ab$  ends with the perpendicular from  $v$  onto  $ab$  (dotted).

of straight-line segments on the boundary of obstacles), then a ray shot from  $b$ . Within  $R$ , we translate  $ab$  parallel to itself to discover the first wavelet on the boundary of  $R$  that is hit – the generator  $v$  of the wavelet is the last vertex on the shortest path to  $ab$ , with the last link of the path being the perpendicular dropped from  $v$  onto  $ab$ . This can be done by computing and storing convex hulls of pairs of consecutive wavelets on the boundary of  $C$ , pairs of pairs, pairs of pairs of pairs, etc., up to the convex hull of the whole component  $C$ . The next paragraph gives the details.<sup>4</sup>

Assume that the wavelets on the boundary of  $C$  are numbered in the order as they appear on the boundary. Compute convex hulls of wavelets 1 and 2, of wavelets 3 and 4, wavelets 5 and 6, etc.; then compute convex hulls of wavelets 1 through 4, wavelets 5 through 8, etc.; ...; finally, compute convex hull of all the wavelets. We thus obtain a hierarchy of convex hulls. Each convex hull of this hierarchy can be built by drawing bitangents to wavelets on the corresponding convex hulls of the preceding level, in  $O(\log n)$  time per bitangent; since the complexity of each level is  $O(|C|)$  and there are  $O(\log n)$  levels, the whole hierarchy, for all connected components of  $C_i$ , can be stored in  $O(n \log n)$  space and computed in  $O(n \log^2 n)$  time. We preprocess each convex hull to answer extreme-wavelet queries – “Which wavelet is first hit by a query line moving in from infinity parallel to itself towards the convex hull?” – in  $O(\log n)$  time (such preprocessing involves simply storing the bitangents to the consecutive wavelets along the convex hull in a search tree, sorted by the slope). Now, the rays shot from  $a$  and  $b$  (the ones that define the region  $R$ ) hit the boundary of  $D_i$  at two wavelets, whose numbers are, say,  $w_1$  and  $w_2$ . The interval  $[w_1, w_2]$  can be covered by  $O(\log n)$  canonical intervals, for which we precomputed and stored the convex hulls; by doing the extreme-wavelet query in each of the intervals we determine the first wavelet between  $w_1$  and  $w_2$  hit by the sliding  $ab$  in overall  $O(\log^2 n)$  time.

<sup>4</sup> Note that while  $R$  may have some obstacles within it or on the boundary (e.g., in Fig. 5 the ray from  $b$  ends at an obstacle), if we sweep  $ab$  parallel to itself, it will first strike the boundary of  $R$  at a point on a circular-arc wavelet (for otherwise there would have been another critical time before the wavefront hit  $ab$ ); thus, we may ignore obstacle edges on the boundary of  $R$ , and focus on storing the convex hulls only of the wavelets.

### 3.3.3 Putting everything together

Our data structure achieves  $P_s = O(n^2 \log n)$ ,  $S_s = O(n^2 \log n)$ ,  $Q_s = O(\log^2 n)$ : the ray shooting data structures and the convex hulls hierarchy require  $O(n \log n)$  time preprocessing and storage per each of the  $O(n)$  critical times, and a query involves finding the relevant  $D_i$  ( $O(\log^2 n)$  time, Section 3.3.1) and then finding the first wavelet hit by the sliding  $ab$  (also  $O(\log^2 n)$ , Section 3.3.2).

### 3.4 Quickest visibility queries

Applying a data structure for SPSQ to QVQ, we obtain a solution for the latter with  $P = P_v + P_s$ ,  $S = S_v + S_s$ ,  $Q = Q_v + KQ_s$ . For instance, using [26] (which provides  $P_v = O(n^2 \log n)$ ,  $S_v = O(n^2)$ ,  $Q_v = O(K \log^2 n)$ ) and the structure from Section 3.3, we obtain  $P = O(n^2 \log n)$ ,  $S = O(n^2 \log n)$ ,  $Q = O(K \log^2 n)$ . See Section 1.2 for other bounds on  $P_v$ ,  $S_v$ ,  $Q_v$ .

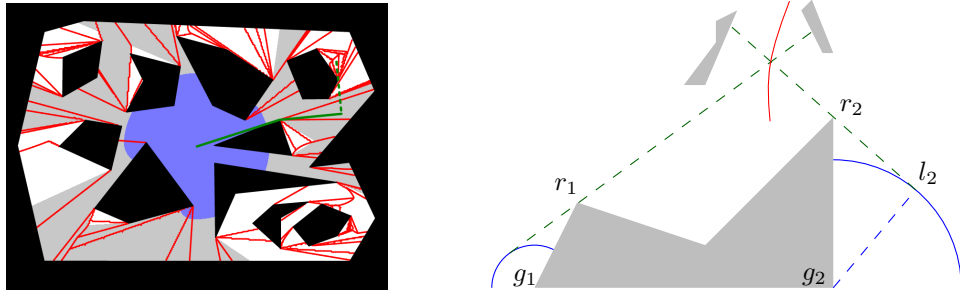
## 4 Quickest visibility map

Assuming the SPM has been built, the quickest way to see a query point  $q$  becomes evident as soon as the following information is specified: the window  $W$  of  $V(q)$  through which to see  $q$  and the vertex  $g$  of  $D$  that is the last vertex on the shortest path to  $W$ . Let  $r$  be the vertex of  $D$  that defines  $W$  (i.e.,  $W$  is part of the ray from  $q$  through  $r$ ); we say that  $r$  is the *root* and  $g$  is the *generator* for  $q$ . We define the *quickest visibility map* (QVM) as the decomposition of  $D$  into cells such that all points within a cell have the same root and generator. That is, within a cell of QVM the answer to QVQ is combinatorially the same: draw the ray from  $q$  through the root  $r$  and drop the shortest segment from the generator  $g$  onto the window (this segment may be perpendicular to the window, or the segment to a window endpoint). In this section we describe an algorithm to build QVM. After the map is preprocessed for point location, QVQs can be answered in  $O(\log n)$  time just by identifying the cell containing the query.

Reusing the idea of continuous Dijkstra algorithm for constructing the SPM we propagate “visibility wave” (v-wave) from  $s$  (Fig. 6, left). Similarly to the geodesic disk (the set of points that can be *reached* from  $s$ , by a certain time, starting from  $s$  and moving with unit speed), we define the *visibility disk of radius  $t$*  as the set of points that can be *seen* before time  $t$  by an observer starting from  $s$  and moving with unit speed. The ball is bounded by extensions of tangents from vertices of  $D$  to circles centered at vertices of the domain; intersections between tangents trace *bisectors* of QVM – a point  $q$  on a bisector can be seen equally fast by going to more than one side of  $V(q)$  (Fig. 6, right).

To bound the complexity of QVM, we first introduce some notation. Let  $r, g$  be the root-generator pair for some cell of QVM. Let  $T$  be the line through  $r$  tangent to the wavelet centered at  $g$  at some time during the p- and v-waves propagation; let  $l$  be the point of contact of  $T$  with the wavelet. The part of the ray  $lr$  after  $r$  running through the free space (if such part exists) is called a *sweeper* – as the wavelet radius grows,  $T$  rotates around  $r$  and (parts of) the sweeper claim the cell(s) of QVM that have  $(r, g)$  as the root-generator pair. We call the segment  $rl$  the *leg* of the sweeper, and the segment  $gl$  (the radius of the wavelet) its *foot* (refer to Fig. 6, right).

Our argument below benefits from the assumption that all angles of the obstacles in  $D$  are larger than  $90^\circ$ ; to satisfy the assumption we can (symbolically) file the domain by replacing each acute vertex with a short edge (see the *corner arc algorithm* [21, Ch. 4] for



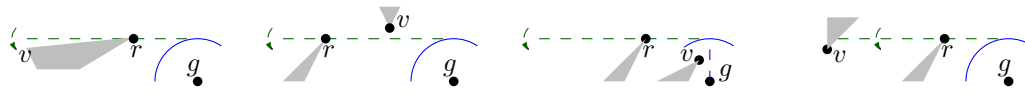
■ **Figure 6** Left: The v-wave is gray, the p-wave is blue ( $s$  is in the center of the rectangle). Red curves are bisectors in the QVM. Solid green shows the shortest path to see a query point; the path ends with a perpendicular dropped from  $D$ 's vertex (the generator) onto the ray (dashed green) from the query point through another vertex of  $D$  (the root). Right: Gray is an obstacle. As p-wave propagates, the geodesic disk grows by expanding the wavelets (blue arcs) at unit speed (wavelets are centered at generators  $g_1, g_2$  and their radii grow at unit speed). Wavelets growth rotates tangents (dashed green) to the wavelets dropped from vertices  $r_1, r_2$  – roots of the QVM cells. The tangents define “shadows” – the boundaries of the visibility disk; the tangents intersection traces the bisector (red) in the QVM. The QVM cell to the left of the bisector has  $(r_1, g_1)$  as the root-generator pair, while the cell on the right has  $(r_2, g_2)$  as the pair; points on the bisector have both  $(r_1, g_1)$  and  $(r_2, g_2)$ , and can be seen equally fast using paths via  $g_1$  and via  $g_2$ .  $g_2 l_2$  is the foot of the sweeper hinged at  $r_2$ ;  $l_2 r_2$  is its leg.

similar ideas). The reason to make the assumption is that the speed of rotation of a sweeper depends on the (inverse of) the length of its leg; in particular, if the length is 0, the sweeper rotates at infinite speed, leading to a discontinuity in v-wave propagation<sup>5</sup>. The filing ensures that the v-wave propagation is continuous, which implies that QVM features (vertices and edges) are due only to intersections of sweepers, or (dis)appearance of sweepers, or possible sweeper extension/contraction as it passes over a vertex of  $D$ .

Consider now the subdivision  $S$  of  $D$  into maximal regions such that for any point inside a region, the set of sweepers that pass over the point is the same (i.e., if  $\aleph(p)$  denotes the set of sweepers that ever pass over  $p$ , then  $S$  is the subdivision into the regions where  $\aleph$  stays the same). The vertices of QVM in the interiors of the regions are the *triple points* where three sweepers (and three bisectors) meet; since a sweeper is defined by two vertices of  $D$  (the root and the generator), there are  $O(n^6)$  triple points.

What remains is to bound the number of vertices of QVM that lie on the edges of  $S$ ; to do that we define a superset  $\bar{S}$  of the edges. Specifically, disappearance of a sweeper may be due to one of the three events (Fig. 7): sweeper becoming aligned with an edge of  $D$  incident to the sweeper's root, the leg's rotation becoming blocked, or the foot's rotation becoming blocked; appearance of a sweeper is due to the reverse of the events. To account for the first-type events we add the supporting lines of edges of  $D$  to  $\bar{S}$ . The second-type events happen on supporting lines of edges of the visibility graph of  $D$ ; we add the lines to  $\bar{S}$ . Third-type events happen on lines through vertices of  $D$  perpendicular to supporting lines of the visibility graph edges; we add these perpendicular lines to  $\bar{S}$ . Finally, extension/contraction of a sweeper happens along the extension of the visibility graph edge. Overall  $\bar{S}$  consists of  $O(nE)$  lines, and all  $O(n^2 E^2)$  of their intersections could potentially be vertices of QVM. The only remaining vertices of QVM are intersections of bisectors with the lines in  $\bar{S}$  (all

<sup>5</sup> See <http://www.cs.helsinki.fi/group/compgeom/qvm/infinitespeed.gif> for an animation



■ **Figure 7** From left to right: Sweeper aligns with  $rv$ ; leg gets blocked by  $v$ ; foot gets blocked by  $v$ ; sweeper extends at  $v$ .

the other vertices are in the interior of the cells of  $S$ ); since any bisector is defined by 4 vertices of  $D$  (2 root-generator pairs for the sweepers defining the bisectors) there are  $O(n^4)$  bisectors. Thus, the total number of vertices of QVM on edges of  $\bar{S}$  (and hence on the edges of  $S$ ) is  $O(n^2E^2 + n^4En)$ .

The overall complexity of QVM (the number of vertices inside the regions of  $S$  plus on the edges of  $S$ ) is thus  $O(n^6 + n^2E^2 + n^5E) = O(n^7)$ . The above description leads to an algorithm to compute the potential  $O(n^7)$  QVM vertices by brute force; for each of them we can check in  $O(n \log n)$  time whether it is indeed a vertex of QVM (see Section 1.2). We then sweep the plane to restore the QVM edges: from each vertex, extend the bisector until it hits another vertex. Putting point location data structure on top of QVM, we obtain  $P = O(n^8 \log n)$ ,  $S = O(n^7)$ ,  $Q = O(\log n)$ .

We note that any algorithm for QVM must have  $P = \Omega(n^4)$ ,  $S = \Omega(n^4)$  because it may need to store explicitly the region weakly visible from a segment, which may have  $\Theta(n^4)$  complexity [40].

## 5 Simple polygons

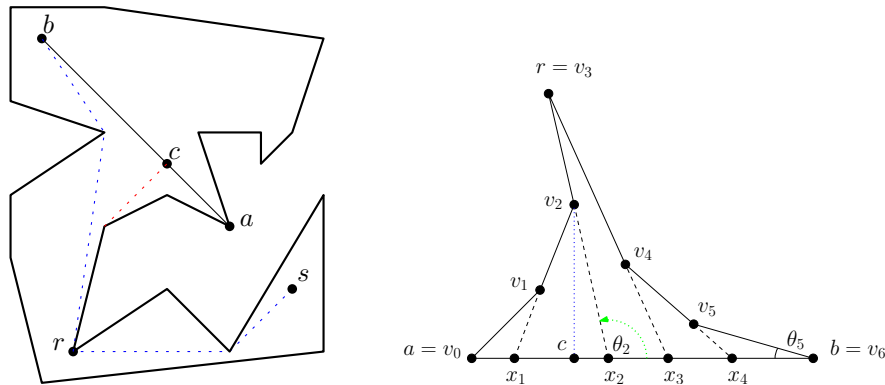
We now present an optimal ( $P_s = O(n)$ ,  $S_s = O(n)$ ,  $Q_s = O(\log n)$ ) algorithm for SPSQs for the case when  $D$  is a simple polygon ( $h = 0$ ); together with the shortest path map of  $D$  and a data structure for ray shooting queries (both can be built in  $O(n)$  time to support  $O(\log n)$ -time queries), it leads to an optimal algorithm ( $P = O(n)$ ,  $S = O(n)$ ,  $Q = O(\log n)$ ) for QVQs as well. We start by introducing additional notation for this section.

Assume that the vertices of  $D$  are stored in an array  $\vec{D}$  sorted in clockwise order along the boundary of  $D$ . For points  $x, y \in D$ , let  $\pi(x, y)$  denote the shortest path between  $x$  and  $y$ ; the shortest path from  $s$  to a point  $y$  is denoted simply by  $\pi(y)$ . Let the predecessor  $\text{pred}(y)$  of  $y$  be the last vertex of  $D$  on  $\pi(y)$  before  $y$  (or  $s$  if  $y$  sees  $s$ ); the predecessor of any point can be read off the shortest path map (SPM) of  $D$  in  $O(\log n)$  time. Let SPT be the shortest path tree from  $s$  in  $D$ ; the tree is the union of paths  $\pi(v)$  for all vertices  $v$  of  $D$ . Assume that the SPT is preprocessed to support lowest common ancestor (LCA) queries in constant time [22].

Let  $ab$  be the query segment. Let  $r$  be the last common vertex of the shortest paths  $\pi(a), \pi(b)$  from  $s$  to the endpoints of the segment;  $r$  can be determined from SPM and SPT in  $O(\log n)$  time: either  $\text{pred}(a) = \text{pred}(b) = r$ , or  $r = \text{LCA}(a, b)$  (Fig. 8, left). The paths  $\pi(r, a)$  and  $\pi(r, b)$  together with the segment  $ab$  form the *funnel*  $F$  of  $ab$ ; the vertex  $r$  is the *apex* of  $F$ .

Let  $a = v_0, v_1, \dots, r = v_m, \dots, v_k, v_{k+1} = b$  be the vertices of the funnel from  $a$  to  $b$ . Note that the paths  $\pi(r, a)$  and  $\pi(r, b)$  are outward convex; in particular,  $F$  can be decomposed into triangles by extending the edges of  $F$  until they intersect  $ab$  (Fig. 8, right). Let  $x_i$  denote the intersection point of the extension of the edge  $v_i v_{i+1}$  with  $ab$  (in particular,  $x_0 = a$  and  $x_k = b$ ). The shortest path from  $s$  to points on the segment  $x_i x_{i+1}$  passes through  $v_{i+1}$  as the last vertex of  $D$ :  $\forall p \in x_i x_{i+1}, \text{pred}(p) = v_{i+1}$ .

Let  $\theta_0, \theta_1, \dots, \theta_k$  denote the angles between the extension edges and  $ab$ :  $\theta_i = \angle b x_i v_i$  for



■ **Figure 8** Left:  $r = LCA(a, b)$ ;  $\pi(c)$  is the answer to the query. Right:  $c$  is the foot of the perpendicular dropped from  $v_2$  to  $ab$ .

$0 \leq i < k$  and  $\theta_k = \pi - \angle abv_k$ . The outward convexity of the paths  $\pi(r, a), \pi(r, b)$  implies that the sequence  $\theta_0, \theta_1, \dots, \theta_k$  is increasing. As a consequence the point  $c \in ab$  closest to  $s$  can be characterized as follows [28]:  $c$  is the foot of the perpendicular from  $v_{i+1}$  to  $ab$  for  $i$  such that  $\theta_i < \pi/2$  and  $\theta_{i+1} \geq \pi/2$ . Thus  $c$  can be found by a binary search on the angles  $\theta_i$ : if  $\theta_i > \pi/2$  then  $c$  lies left of  $x_i$ , whereas if  $\theta_i < \pi/2$  then  $c$  lies right of  $x_i$ . We now describe how to implement the search in  $O(\log n)$  time.

First, if  $\theta_0 > \pi/2$  then  $c = a$ , and if  $\theta_k < \pi/2$  then  $c = b$ ; in both cases we are done. Next, look at the extensions of the edges emanating from the apex  $r = v_m$  of the funnel. If  $\theta_{m-1} \leq \pi/2 < \theta_m$ ,  $c$  is the foot of the perpendicular from  $v_m$  to  $ab$  and we are done.

It remains to show what to do if  $\theta_{m-1} > \pi/2$  (the case  $\theta_{m-1} < \pi/2$  is symmetric). In this case  $\theta_i > \pi/2$  for  $m \leq i \leq k$  since the angle sequence is increasing; in particular  $c$  is the foot of the perpendicular from some vertex  $v_i$  to  $ab$ , where  $v_i$  is on the left side  $\pi(r, a)$  of the funnel  $F$ , i.e.,  $1 \leq i < m$ . To determine  $v_i$  we would like to perform a binary search on the sequence  $v_0, \dots, v_k$ ; however this sequence is not directly accessible (we do not compute it during the query since it can have  $\Omega(n)$  size). We therefore use the array  $\vec{D}$ , and perform a binary search on the interval  $[r, a]$  in  $\vec{D}$  (if  $r = s$  and  $s$  is not a vertex of  $D$ , we take the first vertex  $v$  after  $s$  on the path  $\pi(a)$  and search in the interval  $[v, a]$  instead).

For a vertex  $u$  in this interval we find the vertex  $LCA(u, a)$ , which is one of the vertices  $v_0, \dots, v_m$  on the left edge of the funnel, say  $v_j$ . By computing the angle  $\theta_j$  we can decide if the binary search has to continue to the left or to the right of  $u$ . After  $O(\log n)$  iterations the binary search is narrowed down to an interval between two successive vertices in  $\vec{D}$ . This implies that the point  $v_i$  from which the perpendicular to  $c$  has to be dropped is also determined. (Note that for several successive vertices  $u_l$  in  $[r, a]$  we can get the same vertex  $v_j$  as a result of computing  $LCA(u_l, a)$ ; still, since the total number of vertices in  $[r, a]$  is  $O(n)$ , after  $O(\log n)$  iterations the binary search is narrowed down to an interval between two successive vertices in  $\vec{D}$ .)

### Quickest visibility queries

In a simple polygon,  $s$  is separated from  $q$  by a unique window of  $V(q)$  (unless  $s$  and  $q$  see each other, which can be tested in  $O(\log n)$  time by ray shooting). Since the last edge of the shortest path  $\pi(q)$  is a straight-line segment, one of the window endpoints is  $a = \text{pred}(q)$ ; the endpoint can be read off the SPM of  $D$  in  $O(\log n)$  time. To find the other endpoint  $b$  of the window, shoot the ray  $qa$  until it intersects the boundary of  $D$ ; this also takes

$O(\log n)$  time using the data structure for ray shooting [24]. Once we have the window  $ab$ , our data structure described above finds the (unique) shortest path to the window in additional  $O(\log n)$  time.

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