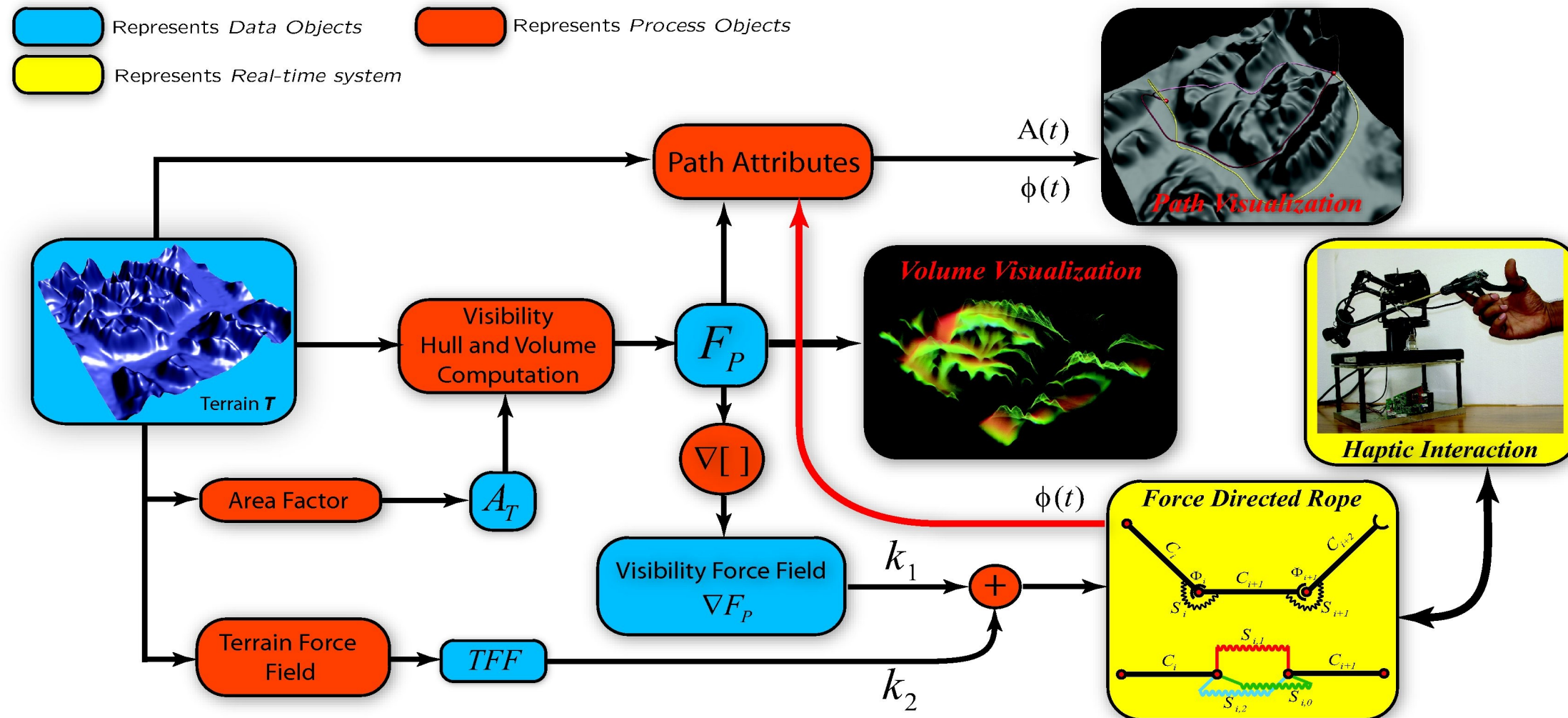# Visibility-guided Interactive Path Optimization

Given a terrain height field T, we compute the visibility field F_p defined as the total terrain area visible from the point p.

We use standard volume rendering techniques for real-time visualization of F_p.

An optimal path between a source and a destination point is computed using a rope simulation component, which is directed by the visibility force field (gradient of F_p).

A haptic device is used to interact with the rope and allow the user to explore the multiple equilibria.

Manohar Srikanth
P.C. Mathias
Vijay Natarajan
Prakash Naidu
Tim Poston