

Fast Obstacle k-Nearest Neighbour Query on Navigation Mesh

Final Presentation

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Summary

1 Introduction

2 New Framework



Outline

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A Introduction



Outline

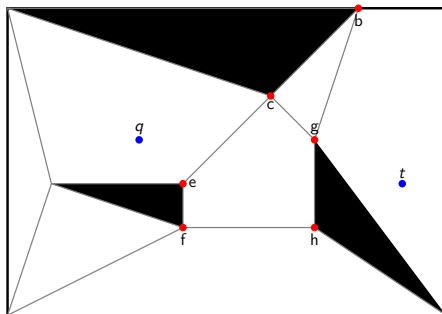
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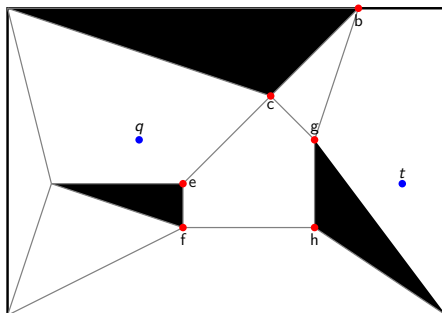
Polyanya: Overview

- q : query point
- t : target
- black polygons are obstacles
- gray border convex polygons are mesh
- mesh: all inside points are visible
- mesh: guides pathfinding



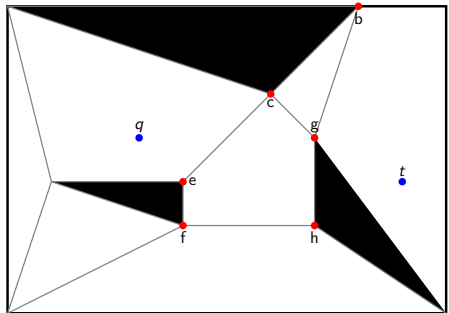
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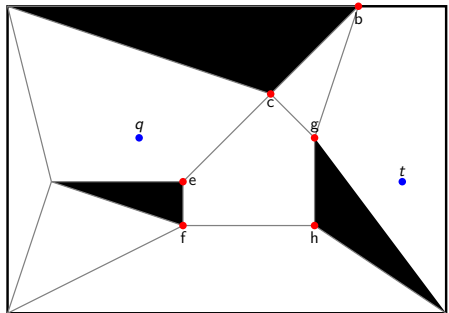
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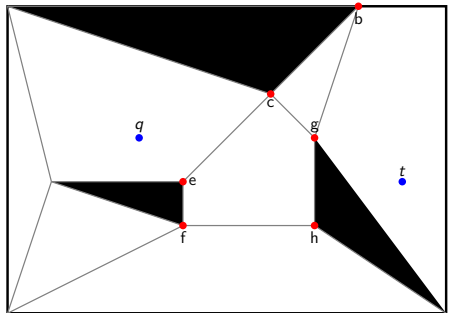
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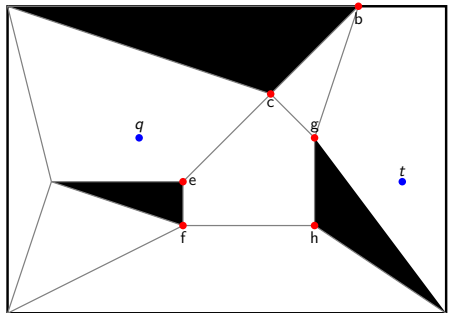
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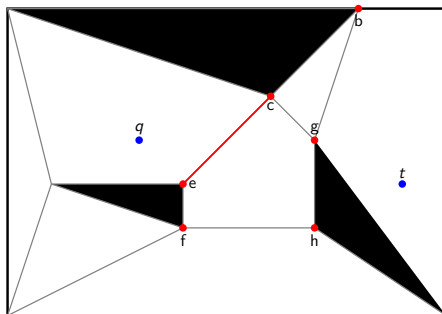
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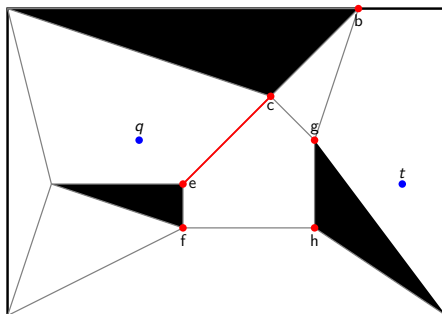
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- root r : $r \in (V \cup \{q\})$
- interval I : on an edge
- all point $\in I$: visible from q



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