

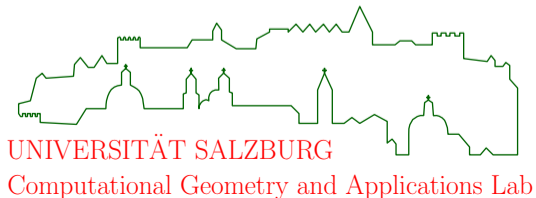
# On Implementing Multiplicatively Weighted Voronoi Diagrams

---

Martin Held<sup>1</sup>   Stefan de Lorenzo<sup>1</sup>

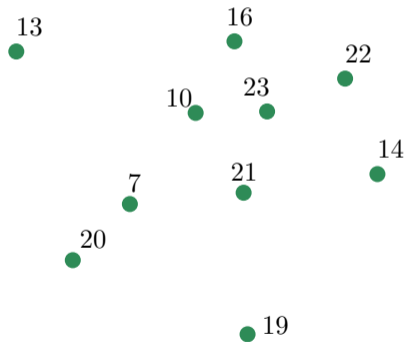
<sup>1</sup>University of Salzburg, Department of Computer Science

March 16, 2020



## Problem

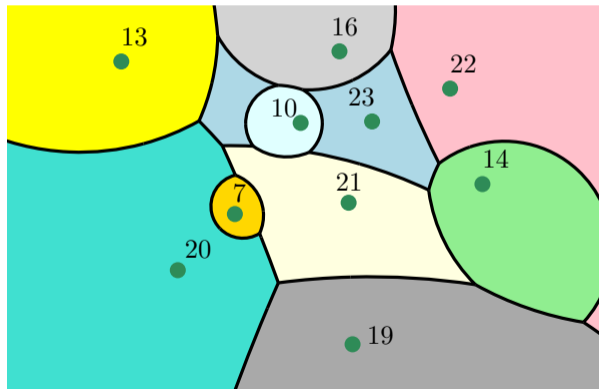
**Given:** A set  $S$  of  $n$  input points in the plane, where every  $s \in S$  is associated with a weight  $w(s) > 0$ .



## Problem

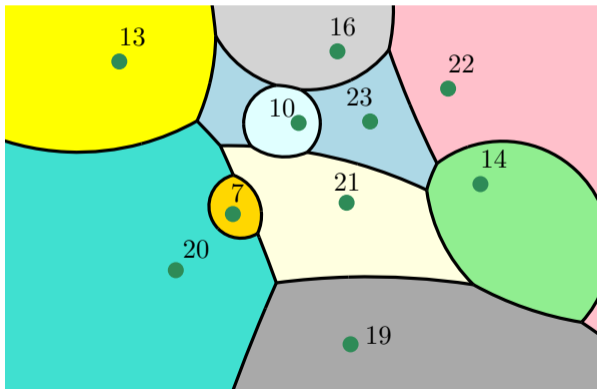
**Given:** A set  $S$  of  $n$  input points in the plane, where every  $s \in S$  is associated with a weight  $w(s) > 0$ .

**Compute:** The multiplicatively weighted Voronoi diagram (MWVD)  $\mathcal{VD}_w(S)$  of  $S$ .



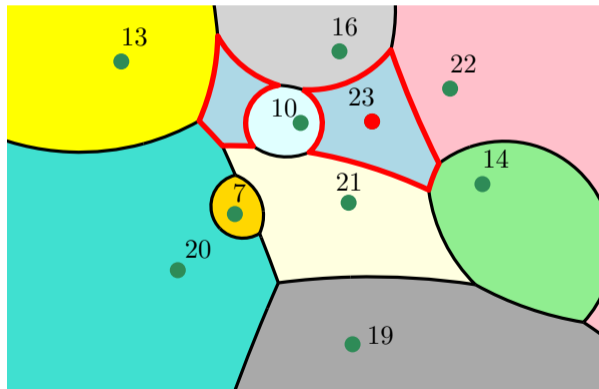
# Multiplicatively Weighted Voronoi Diagrams

- The Voronoi edges are formed by straight-line segments, rays, and circular arcs.

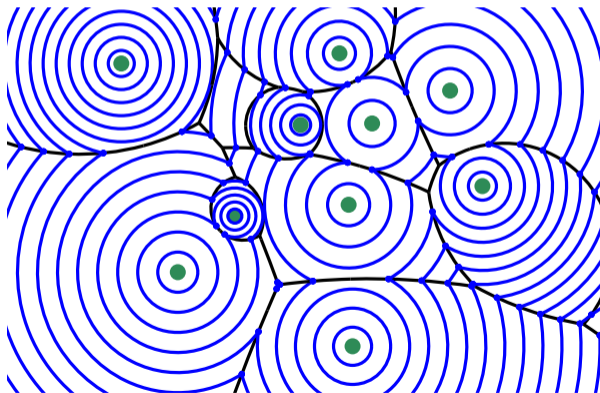


# Multiplicatively Weighted Voronoi Diagrams

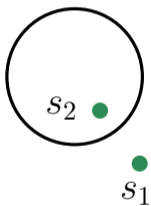
- The Voronoi edges are formed by straight-line segments, rays, and circular arcs.
- The Voronoi regions are (possibly) disconnected.
- The MWVD has a quadratic combinatorial complexity in the worst case.



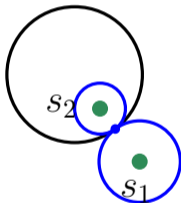
- We present a wavefront-based approach for computing MWVDs.
- The **wavefront** covers an increasing portion of the plane over time.
- It consists of **wavefront arcs** and **wavefront vertices**.
- Whenever a wavefront arc vanishes or spawns, a new Voronoi node is discovered.



- Every site is associated with an *offset circle*.

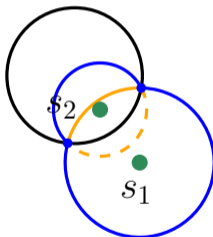


- Every site is associated with an **offset circle**.
- Two **moving intersection points** trace out the bisector as time progresses.

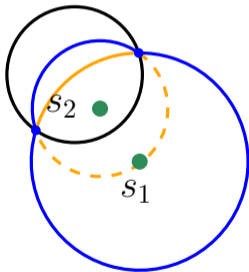




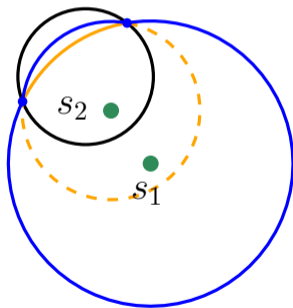
- Every site is associated with an **offset circle**.
- Two **moving intersection points** trace out the bisector as time progresses.
- **Inactive arcs** along the offset circles are eliminated.
- The **active arcs** are stored in sorted angular order.



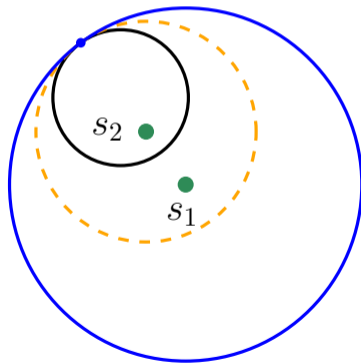
- Every site is associated with an **offset circle**.
- Two **moving intersection points** trace out the bisector as time progresses.
- **Inactive arcs** along the offset circles are eliminated.
- The **active arcs** are stored in sorted angular order.



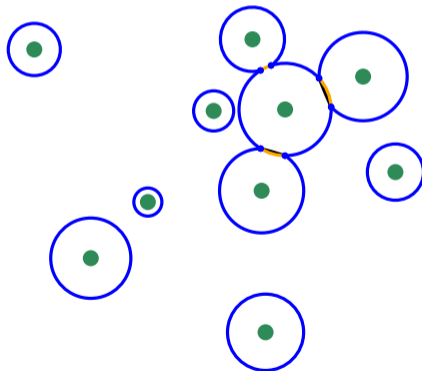
- Every site is associated with an **offset circle**.
- Two **moving intersection points** trace out the bisector as time progresses.
- **Inactive arcs** along the offset circles are eliminated.
- The **active arcs** are stored in sorted angular order.



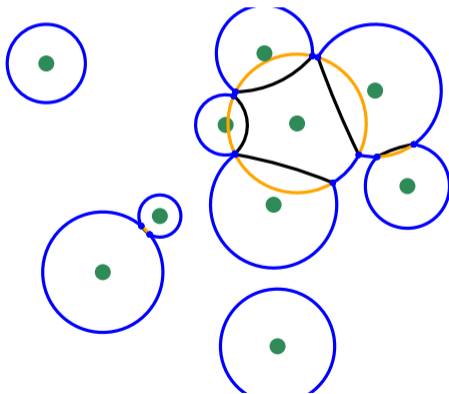
- Every site is associated with an **offset circle**.
- Two **moving intersection points** trace out the bisector as time progresses.
- **Inactive arcs** along the offset circles are eliminated.
- The **active arcs** are stored in sorted angular order.



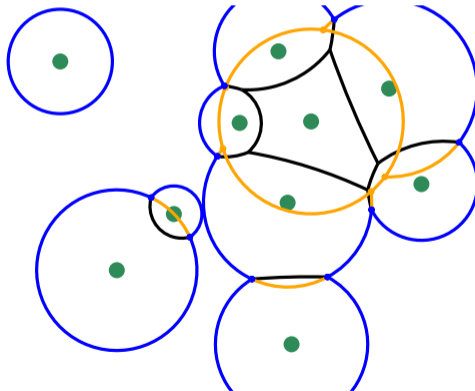
- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



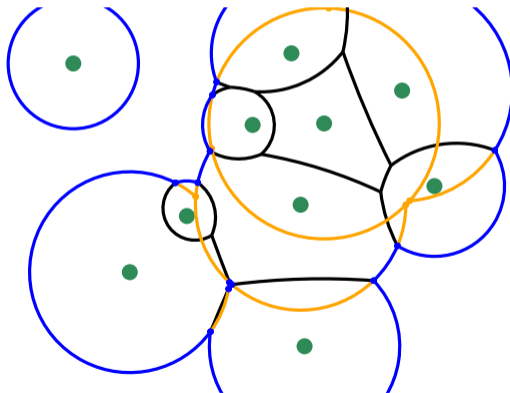
- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.

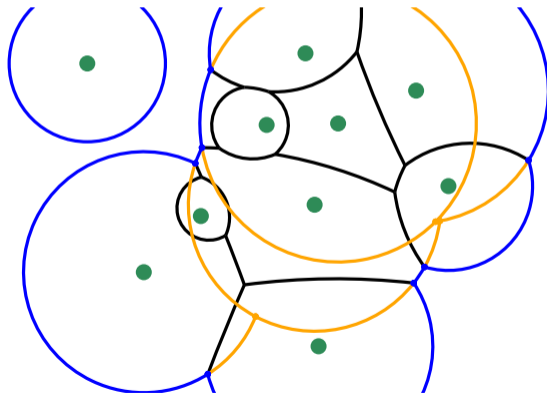


- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.

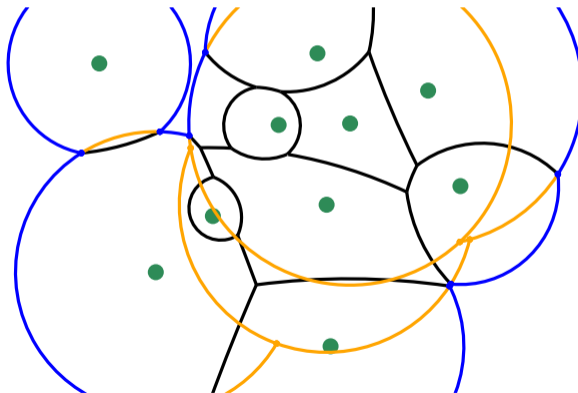




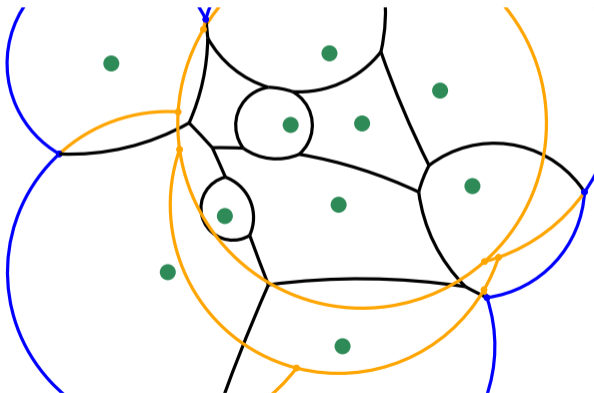
- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



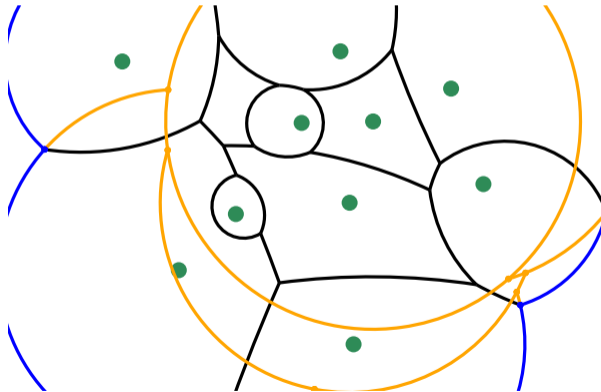
- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



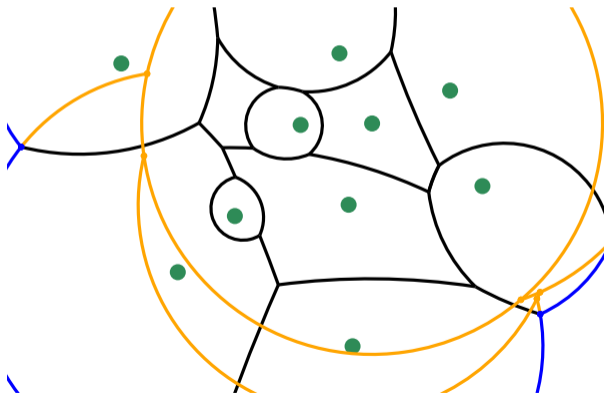
- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



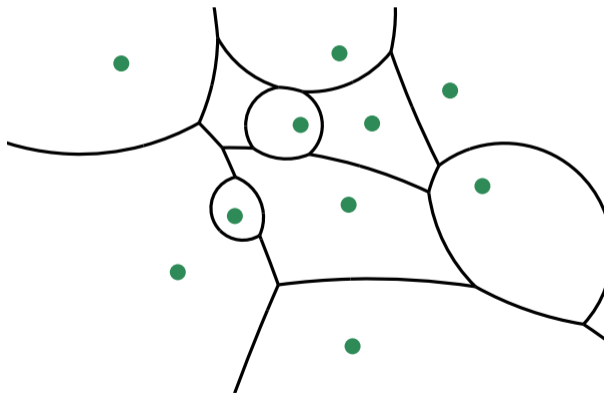
- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.

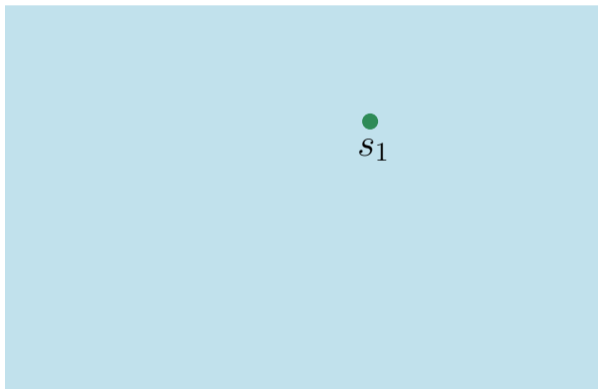


- **Collision** and **domination events** mark the initial and last contact of a two offset circles.
- **Arc events** happen whenever active arcs vanish or spawn.
- These events are stored in a priority queue  $Q$ .
- The angular order of active arcs only changes at events.



- All topological changes of the wavefront are properly detected.
- A quadratic number of collision events are computed in any case.
- A moving intersection can be charged with a constant number of arc events.
- In the worst case  $\mathcal{O}(n^2)$  arc events take place.
- All events can be handled in  $\mathcal{O}(\log n)$  time.
- Therefore, the algorithms runtime is  $\mathcal{O}(n^2 \log n)$  in the worst case.

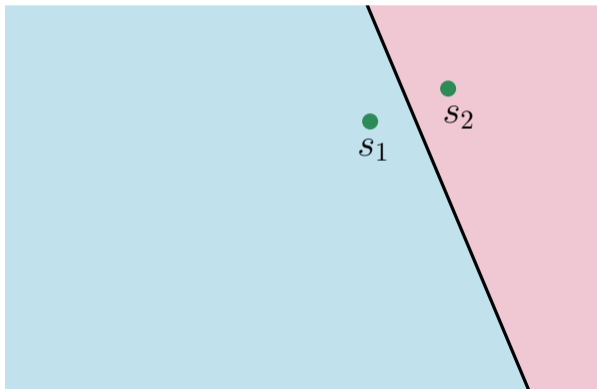
- A vast number of collisions are invalid for general input.
- The calculation of all possible collision requires a high computational effort.
- Invalid collision are filtered in an additional preprocessing step.
- Thus, the average case behavior of the algorithm is improved.





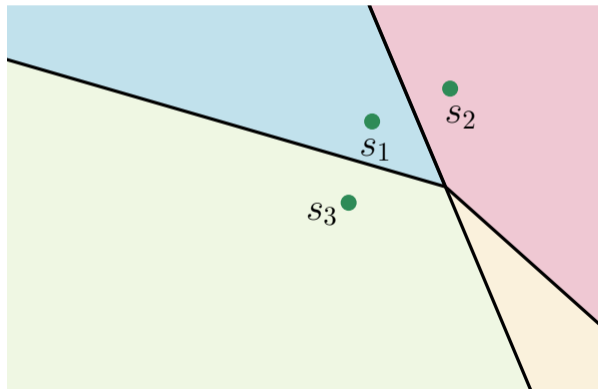
## Reducing the Number of Collisions

- A vast number of collisions are invalid for general input.
- The calculation of all possible collision requires a high computational effort.
- Invalid collision are filtered in an additional preprocessing step.
- Thus, the average case behavior of the algorithm is improved.



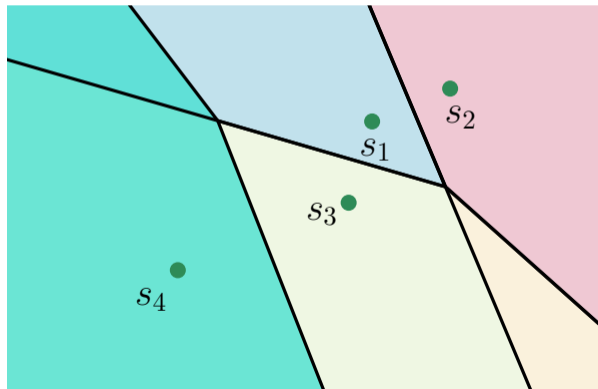
## Reducing the Number of Collisions

- A vast number of collisions are invalid for general input.
- The calculation of all possible collision requires a high computational effort.
- Invalid collision are filtered in an additional preprocessing step.
- Thus, the average case behavior of the algorithm is improved.



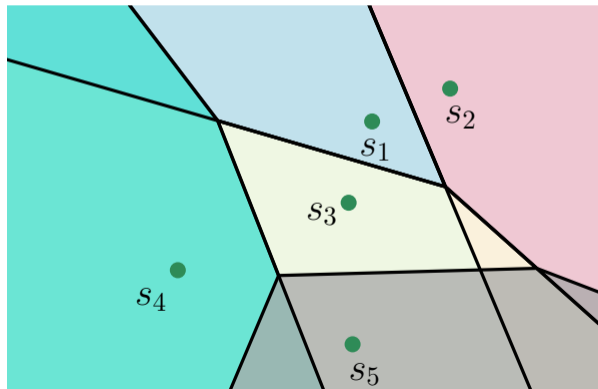
## Reducing the Number of Collisions

- A vast number of collisions are invalid for general input.
- The calculation of all possible collision requires a high computational effort.
- Invalid collision are filtered in an additional preprocessing step.
- Thus, the average case behavior of the algorithm is improved.



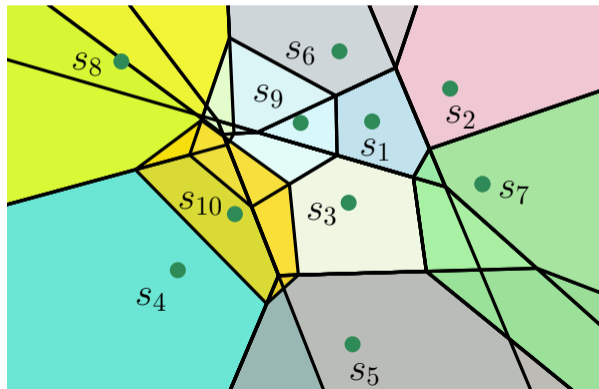
## Reducing the Number of Collisions

- A vast number of collisions are invalid for general input.
- The calculation of all possible collision requires a high computational effort.
- Invalid collision are filtered in an additional preprocessing step.
- Thus, the average case behavior of the algorithm is improved.

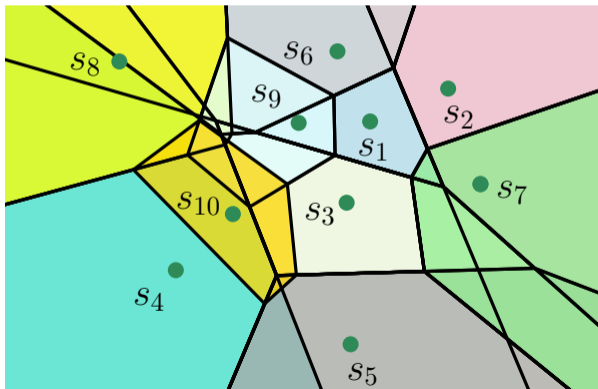


## Reducing the Number of Collisions

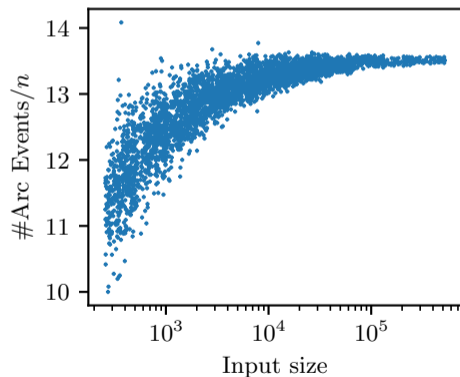
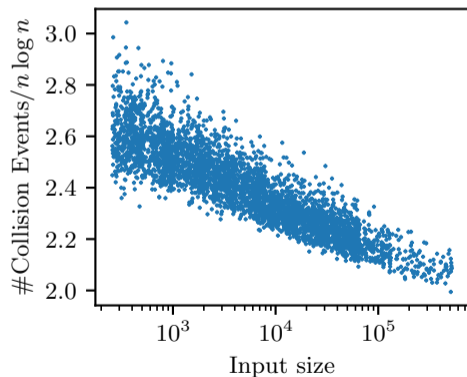
- A vast number of collisions are invalid for general input.
- The calculation of all possible collision requires a high computational effort.
- Invalid collision are filtered in an additional preprocessing step.
- Thus, the average case behavior of the algorithm is improved.



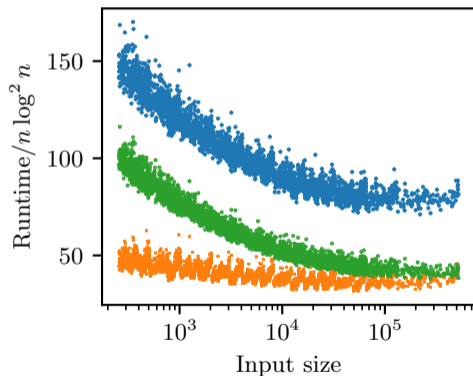
- Only sites within the same candidate set may collide.
- A candidate set contains  $\mathcal{O}(\log n)$  many sites in the expected case [HPR15].
- The expected complexity of overlay arrangement is bound by  $\mathcal{O}(n \log n)$  [KRS11].
- Thus, it is necessary to compute  $\mathcal{O}(n \log^3 n)$  many collisions.



- The implementation is based on the Computational Geometry Algorithms Library (CGAL).
- We tested our strategy on 3800 randomly generated inputs.
- All tests were carried out on an Intel Core i7-6700 clocked at 3.40GHz.



- The implementation is based on the Computational Geometry Algorithms Library (CGAL).
- We tested our strategy on 3800 randomly generated inputs.
- All tests were carried out on an Intel Core i7-6700 clocked at 3.40GHz.



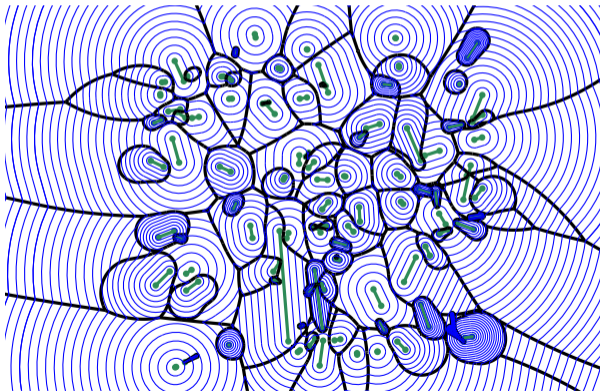
Overlay arrangement

Event queue

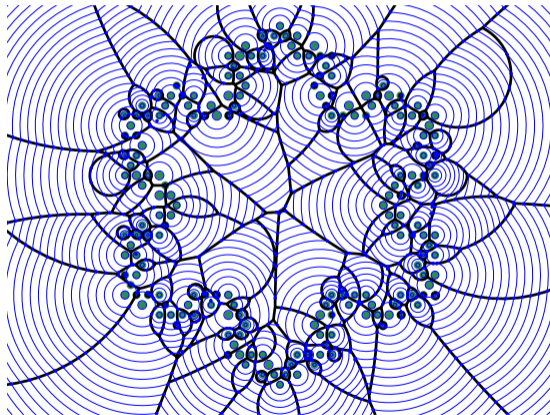
Overall runtime



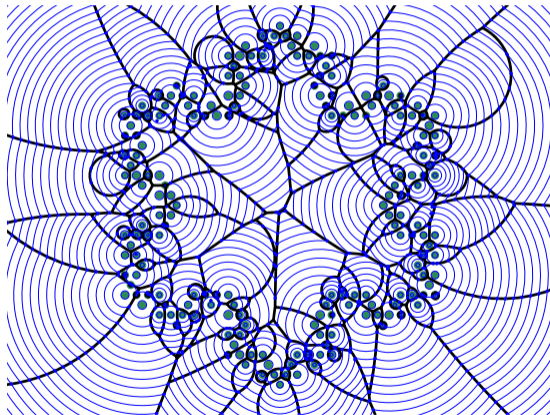
- Our (basic) algorithm is also able to deal with additive weights.
- The strategy can be easily extended to also handle weighted straight-line segments.



- We propose a fast, practical strategy to compute MWVDs.
- The expected runtime is improved by using an overlay arrangement.
- We provide a robust implementation using exact arithmetic.



- We propose a fast, practical strategy to compute MWVDs.
- The expected runtime is improved by using an overlay arrangement.
- We provide a robust implementation using exact arithmetic.



**Thank you for your attention!**



Sariel Har-Peled and Benjamin Raichel.

On the Complexity of Randomly Weighted Multiplicative Voronoi Diagrams.

*Discrete Comput. Geom.*, 53(3):547–568, 2015.



Haim Kaplan, Edgar Ramos, and Micha Sharir.

The Overlay of Minimization Diagrams in a Randomized Incremental Construction.

*Discrete Comput. Geom.*, 45(3):371–382, 2011.