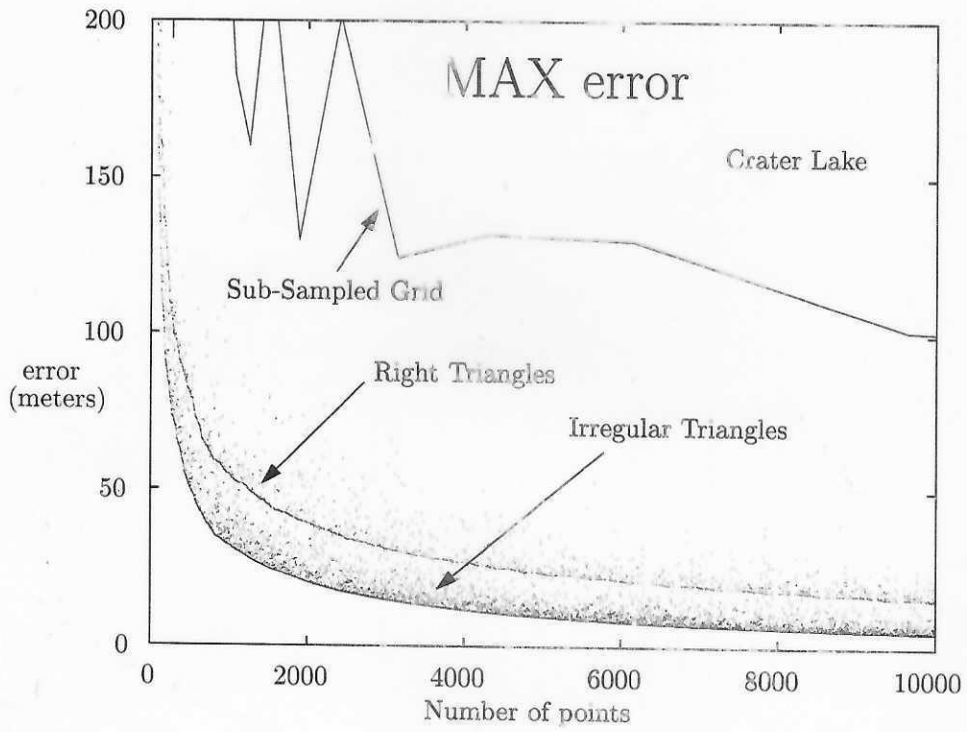
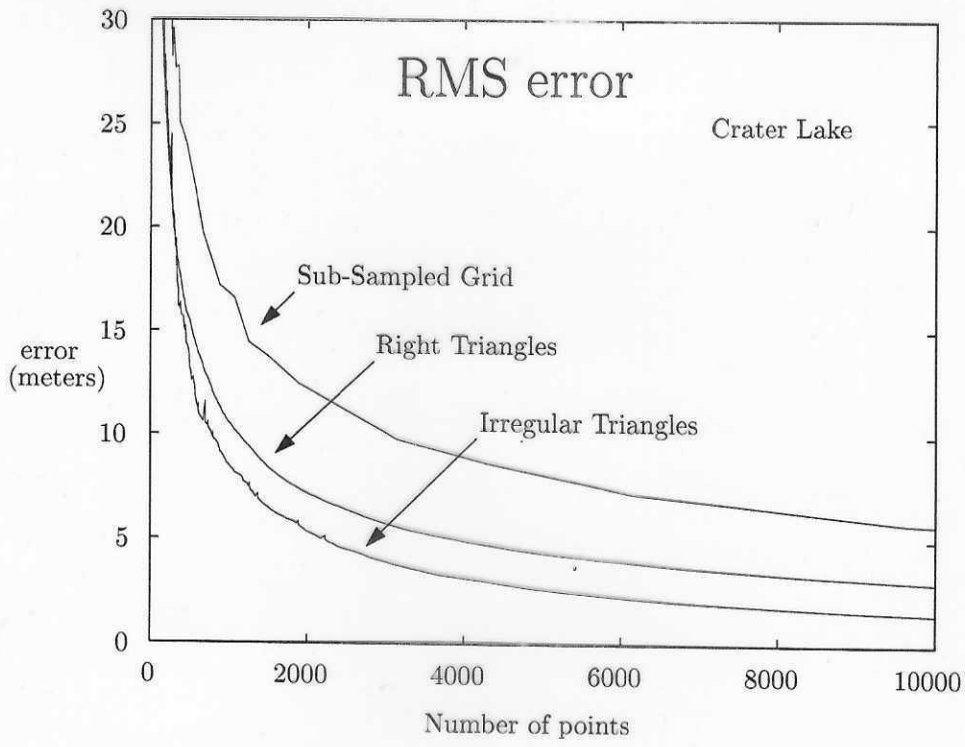


Error vs. number of points



View Sensitive Approximation

Visible Error



Triangle t is bad if it's in Field of View and

$$\frac{h_t}{d_t} > \text{errThreshold}$$

or

$$\frac{|t|}{d_t} > \text{sizeThreshold}$$

size of triangle

Create approximation with no bad triangles

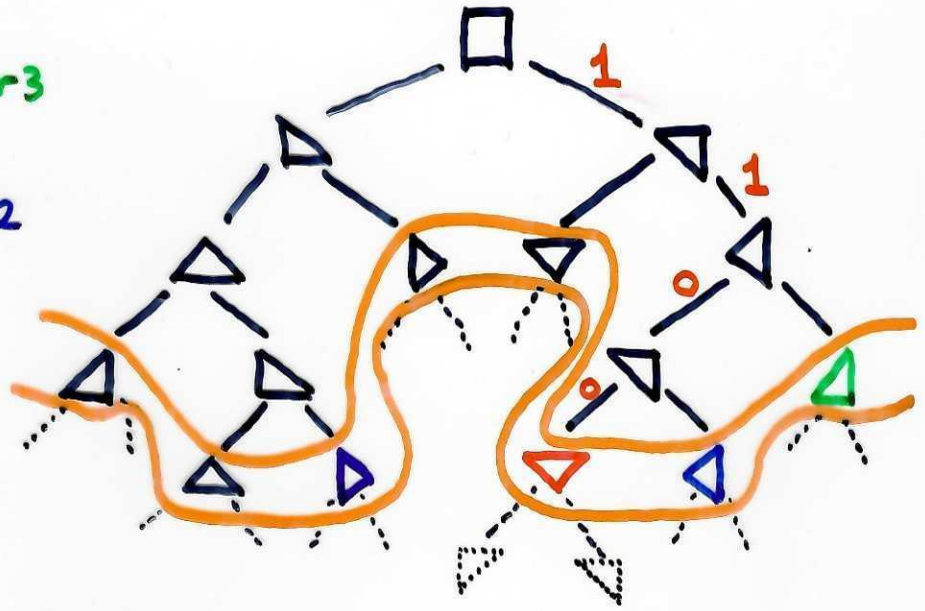
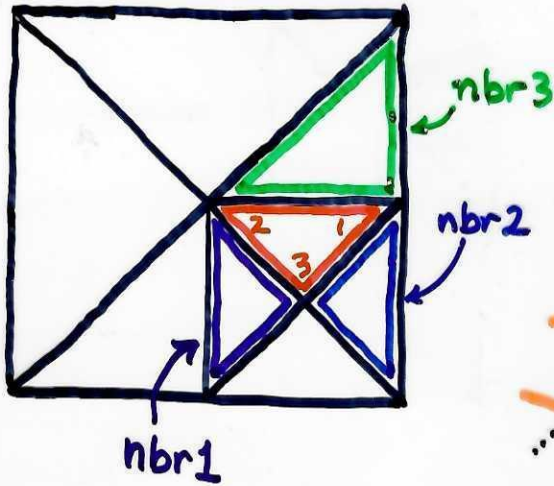
[Badness changes as viewer moves]

SPACE

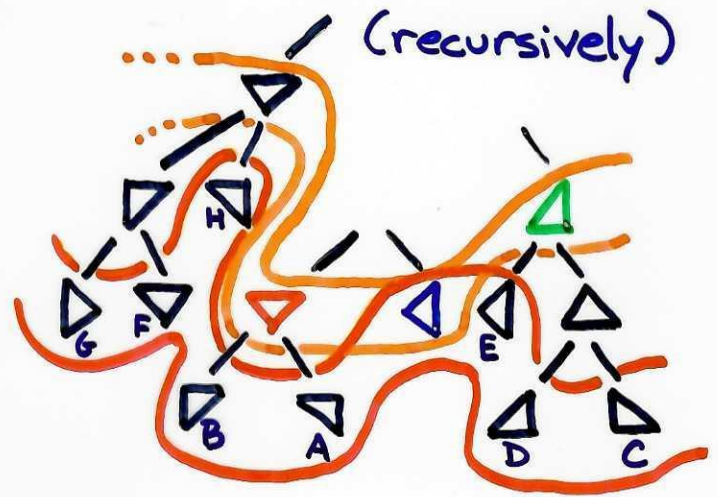
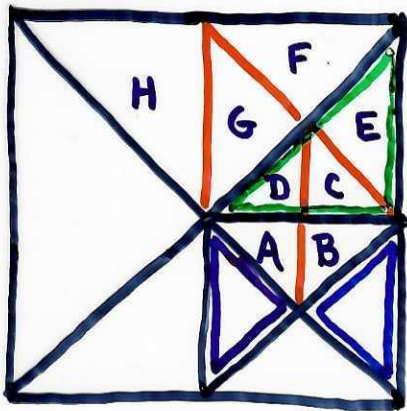
+2 bytes per Δ to store h (max. error)

Fast Approximation

Top-Down (depth-first search) approach



Propagate Split to neighbor 3



How to determine addresses of neighbors

- Store 3 pointers (12 bytes) per Δ **BAD**
- OR • Calculate neighbor address from Δ address **GOOD**