

# Routenplanung durch Flächen

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Passau, 22. März 2017



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# Bisherige Ansätze

(Auswahl)

Roland Olbricht:

- Braucht OpenStreetMap Flächen und Kanten?

Anita Graser:

- Developing an Open Pedestrian Landmark Navigation Model
- Integrating Open Spaces into OpenStreetMap Routing Graphs for Realistic Crossing Behaviour in Pedestrian Navigation

Dzenan Dzafic:

- Routing über Flächen mit SpiderWebGraph

# Routenplanung



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# Routenplanung





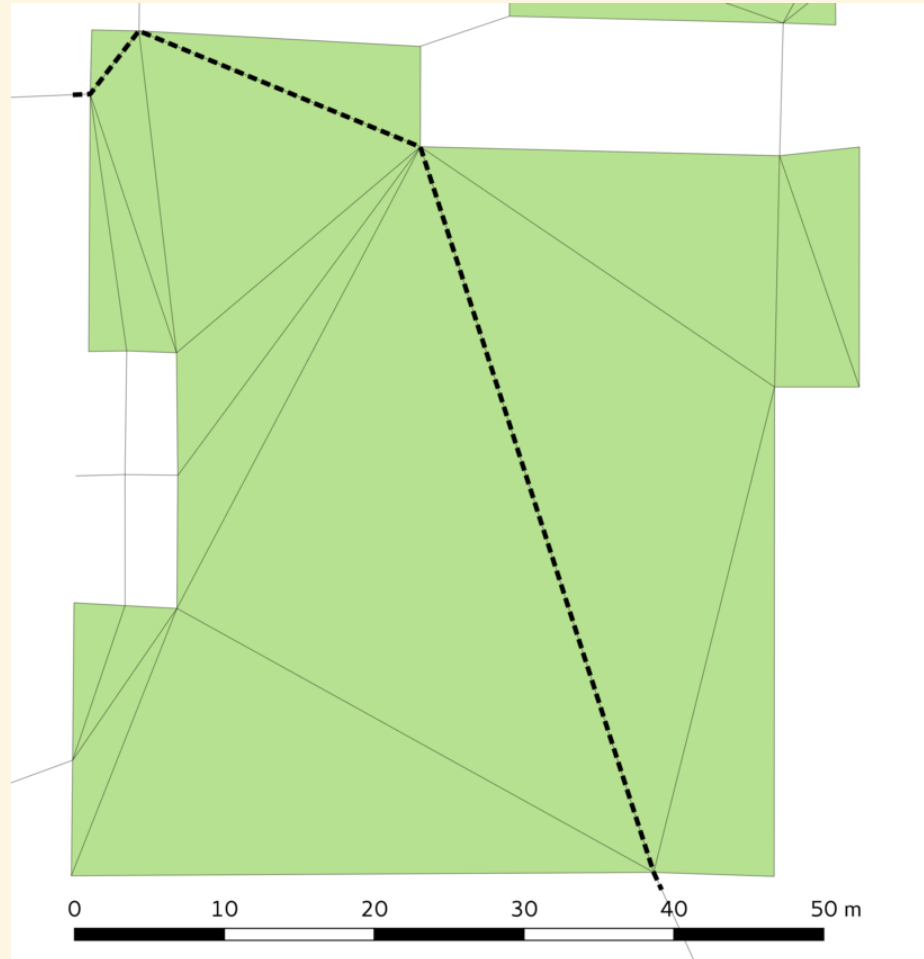
# Routenplanung



# Polygon-Rand

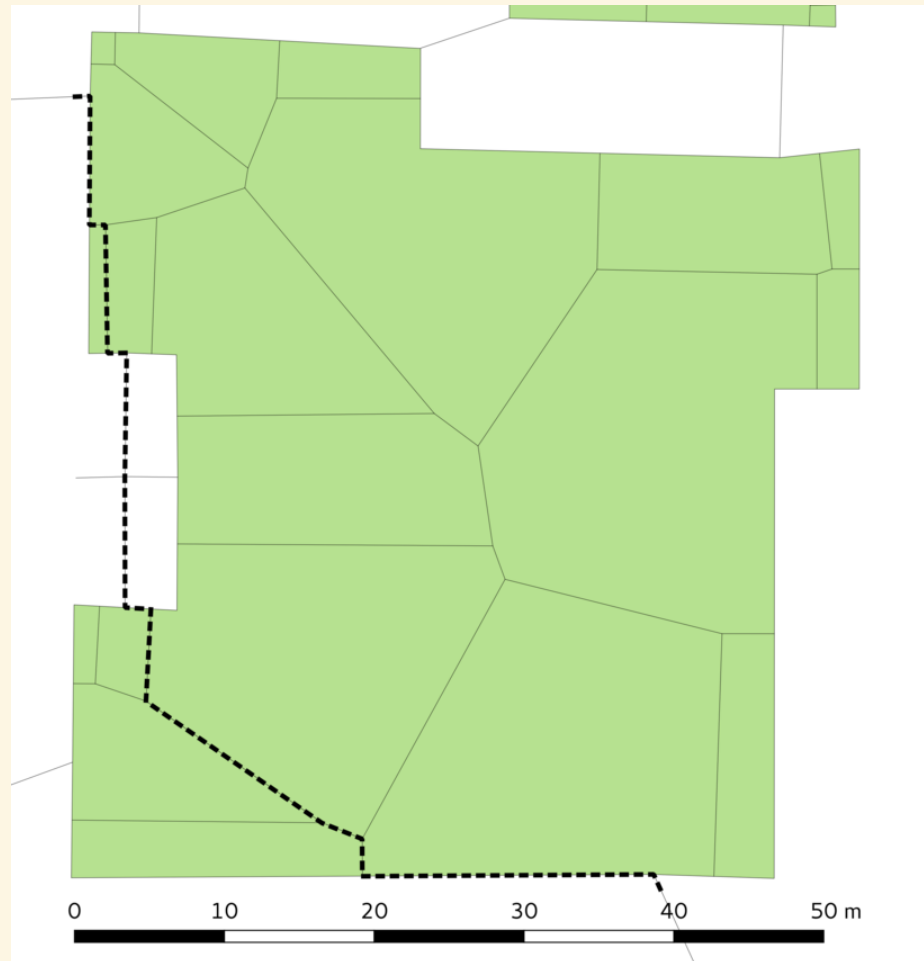


# Delaunay





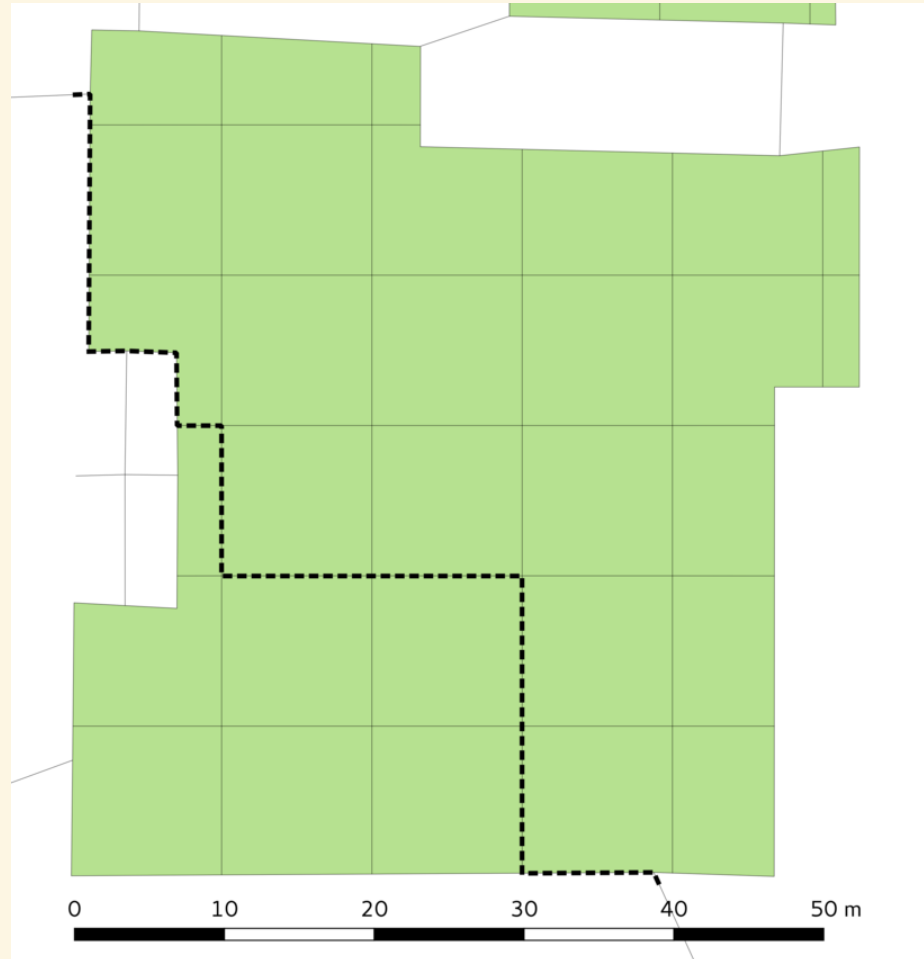
# Voronoi



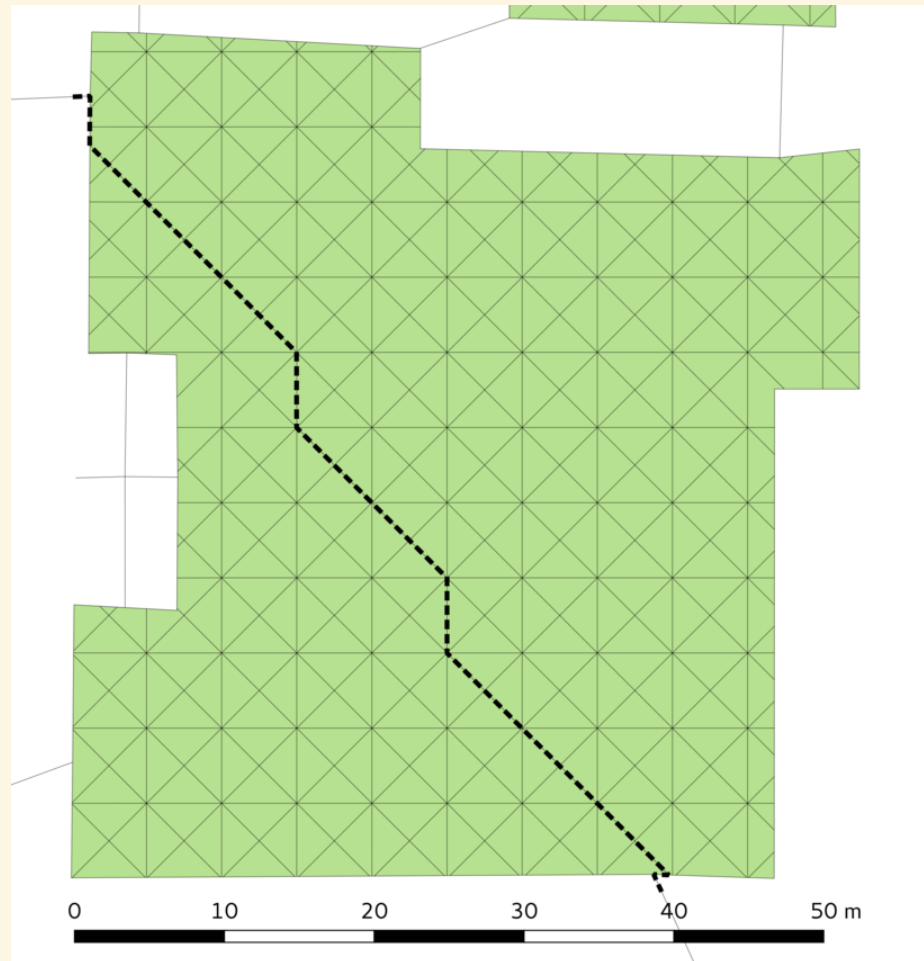
# Skeleton



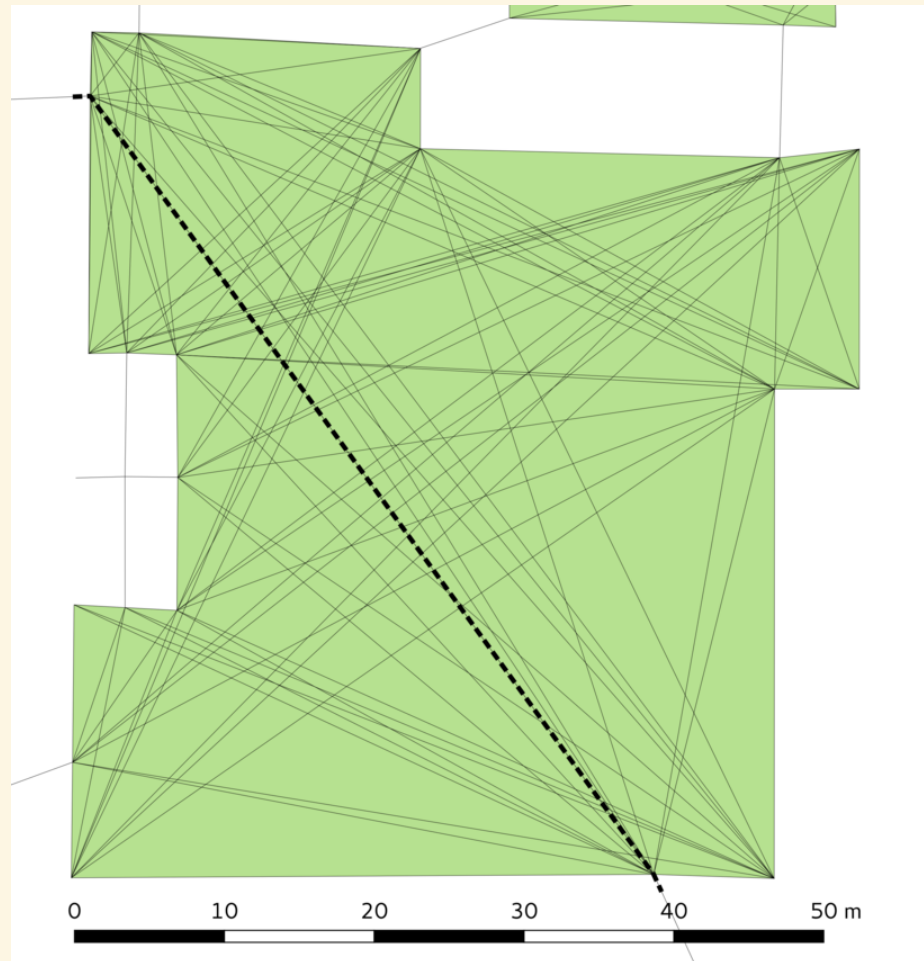
# Grid



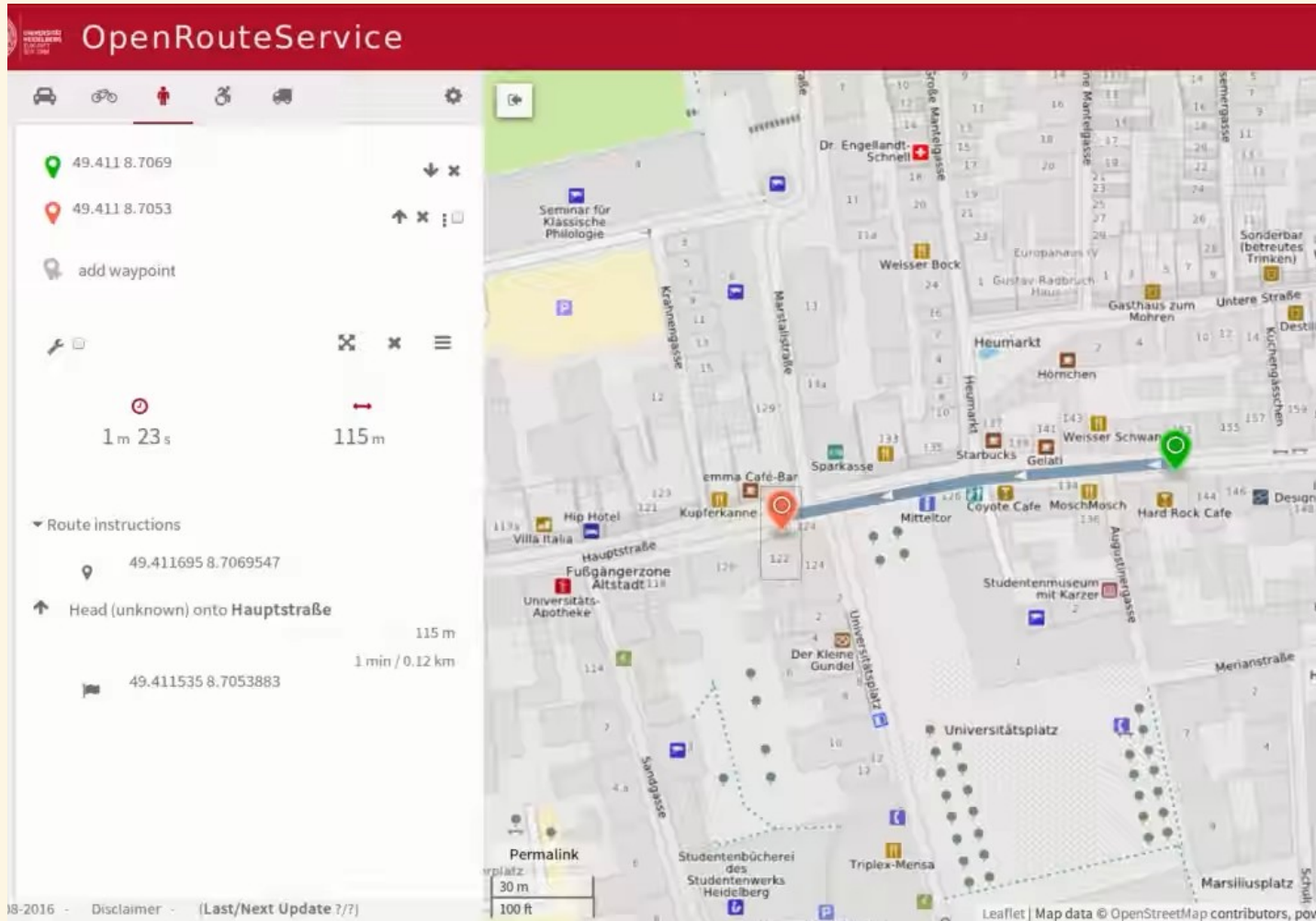
# Spider-Grid



# Visibility



# Visibility

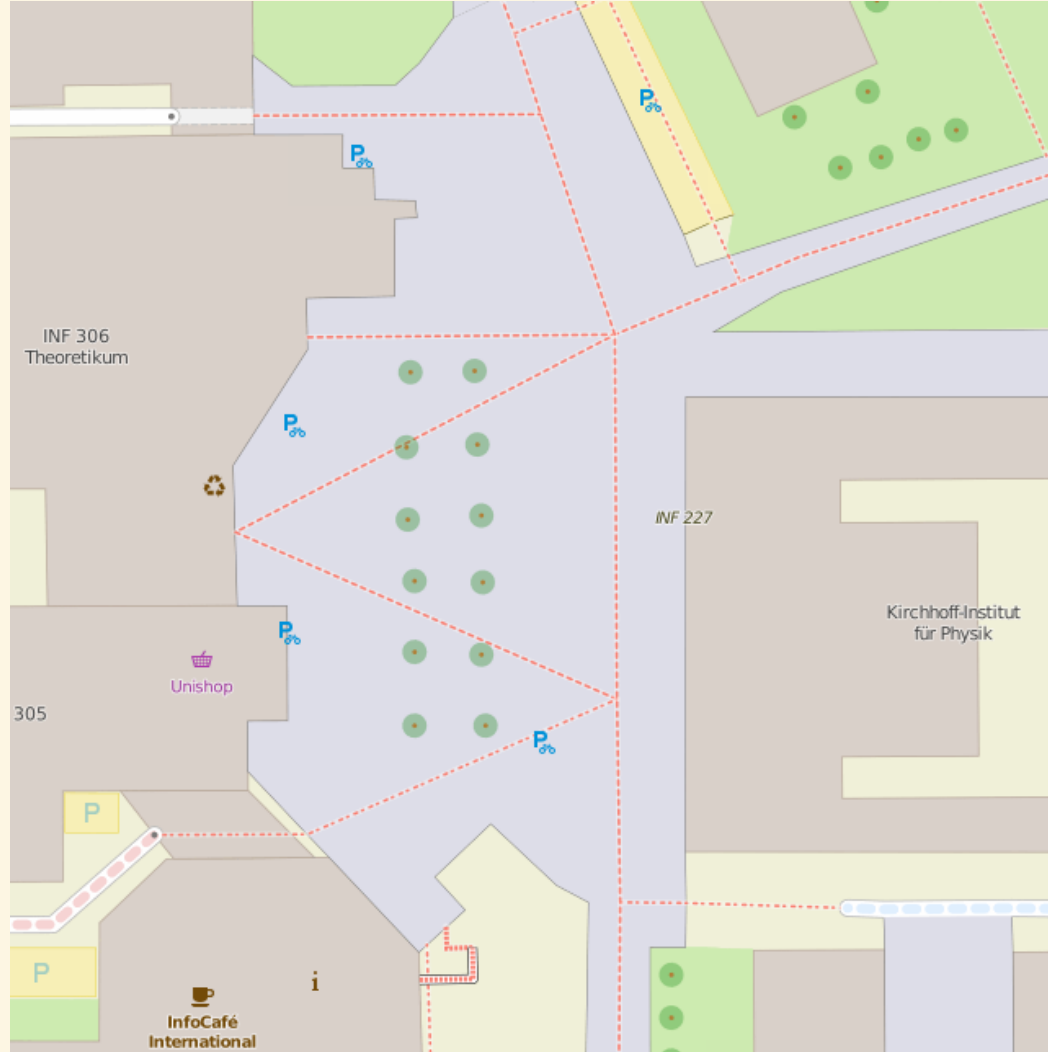




# Spider-Grid

The screenshot displays the OpenRouteService interface. The top navigation bar includes icons for car, bicycle, pedestrian, wheelchair, and truck, along with a settings gear and a spider-grid icon. The left sidebar shows two waypoints: 49.411 8.7071 (green pin) and 49.411 8.7052 (red pin). Below the waypoints are controls for adding a waypoint, zooming, and a scale bar showing 1 m and 38 s. The 'Route instructions' section shows the first instruction: 'Head (unknown) onto Hauptstraße' with a distance of 137 m and a time of 2 min / 0.14 km. The main map area shows a spider-grid route (dotted line) connecting various points in Heidelberg, including the University of Heidelberg and the city center. A blue line indicates the current route segment. The map includes labels for streets like Hauptstraße, Universitätsplatz, and Marsiliusplatz, and landmarks like the Studentenmuseum and Neue Universität. A scale bar at the bottom left shows 30 m and 100 ft. The footer contains a disclaimer, update information '(Last/Next Update 7/?)', and copyright information for OpenStreetMap contributors.

# virtuelle Wege



# Platz nicht angeschlossen

