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A Polynomial Algorithm for Subisomorphism of Holey Plane Graphs

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Abstract

We address the problem of searching for a pattern in a plane graph, that is, a planar drawing of a planar graph. We define plane subgraph isomorphism and give a polynomial algorithm for this problem. We show that this algorithm may be used even when the pattern graph has holes.

1. Introduction

Many applications involve mining graphs in order to discover frequent connected subgraphs. If this problem may be solved in output-polynomial time for some specific classes of graphs such as trees (Chi et al., 2005), tenuous outerplanar graphs (Horvath et al., 2006), or bounded treewidth graphs (Horvath & Ramon, 2008), it remains challenging in the general case. This mainly comes from the fact that subgraph isomorphism is NP-complete in the general case.

In this paper, we extend Damiand et al. (2009)’s algorithm to solve the sub-isomorphism problem for plane graphs with holes.

2. Plane Graphs

A graph is a pair $G = (V, E)$ where $V$ is a set of vertices and $E$ is a set of edges. Below, all the graphs are supposed connected, that is, every pair of vertices is linked by a sequence of edges.

A planar embedding of a graph $G$ is an injective mapping $\phi$ that assigns 2D points to vertices, and 2D curves to edges. $G$ is planar if an embedding exists such that no two embedded edges intersect, except at their endpoints. A theorem by Fáry (1948) states that given a non-crossing representation of a planar graph, it is always possible to move the vertices so that the edges are drawn with straight-line segments. Hence, we only consider planar embeddings such that embedded edges are straight-line segments that are defined by the 2D embedding of their endpoint vertices.

Several embeddings may however exist for a graph. A plane graph is a triple $G = (V, E, \phi)$ such that $(V, E)$ is

A planar graph and $\phi : V \to \mathbb{R}^2$ is an embedding of the vertices such that no two embedded edges intersect, except at their endpoints.

A plane graph is made of (bounded or unbounded) faces: when considering the planar embedding, the complement of the set of edges is a disjoint union of simply connected regions called faces. Formally, a compact plane subgraph isomorphism problem deciding whether $G_p$ is isomorphic to some subgraph of $G_t$ is made of 9 faces: Faces connected. This algorithm is derived from an algorithm that solves the sub-isomorphism problem for combinatorial maps. Combinatorial maps were introduced in the early 60’s to efficiently implement plane graphs (Edmonds, 1960; Tutte, 1963). They describe the topological organisation of plane graphs by decomposing every edge into two darts (i → j) and (j → i), and by using two functions $\beta_1$ and $\beta_2$ which respectively define dart successions in face boundaries and face connectivity (see Fig. 4).

The algorithm proposed in (Damiand et al., 2009) for solving the submap isomorphism problem is based on the fact that, given any starting dart, the traversal of a combinatorial map (that is, the order in which darts are discovered) is unique, provided that one has fixed (1) the strategy used to memorize darts that were discovered but not exploited yet (e.g., Last In First Out / LIFO), and (2) the order in which $\beta_1$ and $\beta_2$ are used to discover new darts (e.g., $\beta_1$ before $\beta_2$).

Hence, to determine if a pattern map $M_p$ is sub-isomorphic to a target map $M_t$, we choose a starting dart $d_p$ in $M_p$, and for every dart $d_t$ of $M_t$, we perform a traversal of $M_p$ starting from $d_p$, and a traversal of $M_t$ starting from $d_t$. Each time a new dart is discover-
Figure 5. Finding a car in an image: The original image, coming from the MOV1 dataset (Luo et al., 2003), is on the left. The plane graph obtained after segmentation is on the middle. The car has been extracted and rotated on the right. It is found again in the original image using Damiand et al. (2009)’s algorithm.

We define the plane subgraph isomorphism for graphs with holes as follows. Consider a pattern compact plane graph \( G_p \) = \((V_p, E_p, \phi_p)\), a set of required faces \( \mathcal{F} \subseteq \text{faces}(G_p) \), and a target plane graph \( G_t = (V_t, E_t, \phi_t) \). Let \( V_{\mathcal{F}}^p \) denote the set of vertices that appear in \( \mathcal{F} \) and \( E_{\mathcal{F}}^p \), the corresponding set of edges. One should find a mapping \( h : V_{\mathcal{F}}^p \rightarrow V_t \) such that (i) \( h \) is an injection, (ii) \( h \) preserves edges, i.e., \( \forall \{x, y\} \in E_{\mathcal{F}}^p \) one has \( \{h(x), h(y)\} \in E_t \), (iii) \( h \) preserves the faces of \( \mathcal{F} \), i.e., for every face \( f \in \mathcal{F} \), there exists a face \( g \in \text{faces}(G_t) \) such that for every edge \( \{x, y\} \in \text{boundary}(f) \), one has \( \{h(x), h(y)\} \in \text{boundary}(f) \).

For example, in Fig. 2, the graph obtained from \( G_1 \) by eliminating faces \( D \) and \( H \) (thus, setting \( \mathcal{F} = \{A, B, C, E, F, G\} \)) would be a plane graph with holes and a face-connected subgraph of graph \( G_1 \).

The algorithm for deciding the plane subgraph isomorphism problem for graphs with holes is derived from the submap isomorphism algorithm of (Damiand et al., 2009) as follows: in the traversal of the pattern graph, the faces that do not belong to the set of required faces \( \mathcal{F} \) must not considered. Note that the set of required faces \( \mathcal{F} \) has to be face-connected.

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**References**


