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To cite this version:

HAL Id: ujm-00411610
https://hal-ujm.archives-ouvertes.fr/ujm-00411610
Submitted on 9 Jun 2011

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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 \( \mathcal{NP} \)-complete in the general case.

In this paper, we focus on plane graphs, i.e., planar graphs that are embedded in planes. Indeed, when graphs model objects defined on planes, such as images, one may consider the planar embedding of the graph. In (Damiand et al., 2009), we have defined and studied the plane (sub)graph isomorphism problem. We have shown that it can be solved in quadratic time whenever the pattern graph is compact, that is, the pattern graph may be obtained by iteratively removing nodes and edges that are incident to the unbounded face.

However, compact plane graphs are somehow restricted, because they do not have any hole. Thus, it would be impossible to use compact plane graphs to model and search for a cup with a handle for instance (see Fig. 1). Indeed, the background of the cup, visible through the handle, would be integrated to the modelling graph, so that the cup could not be searched independently of the background.

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 compact plane subgraph isomorphism problem be-
fried when walking along the boundary of
A face-connected plane graph
we note
the plane graph of Fig. 2 is made of 9 faces: Faces
A to H are bounded whereas the white face is un-
bounded (given in Fig. 2).

3. Compact Plane Subgraph
Isomorphism and Combinatorial
Maps

A compact plane subgraph isomorphism problem
between a pattern plane graph \( G_p = (V_p, E_p, \phi_p) \) and a
target plane graph \( G_t = (V_t, E_t, \phi_t) \) consists in de-
ciding whether \( G_p \) is isomorphic to some subgraph of \( G_t \),
which is obtained from \( G_t \) by iteratively re-
moving nodes and edges that are adjacent to the un-
bounded face (see Fig. 3).

Figure 2. A face-connected plane graph \( G_1 \) with 8 bounded
faces (labeled from A to H) and 1 unbounded (white) face.

Figure 3. A face-connected plane graph \( G_2 \) which is a com-
 pact subgraph of \( G_1 \) (given in Fig. 2).

Figure 4. An example of combinatorial map. Darts are rep-
resented by numbered segments. Concerning functions \( \beta_1 \)
and \( \beta_2 \), consider e.g. dart 11; one has \( \beta_1(11) = 8 \) and
\( \beta_2(11) = 12 \).

boundary(f), one has \( \{h(x), h(y)\} \in \text{boundary}(f) \).

In (Damiand et al., 2009), we have proposed a poly-
nomial algorithm for the plane subgraph isomorphism
problem where the pattern graph \( G_p \) must be face-
connected. This algorithm is derived from an algo-

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 explored 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 discov-
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.

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 \( h : V^\mathcal{F}_p \to V_t \) 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.

Acknowledgments

This work was supported in part by the IST Programme of the European Community, under the PASCAL 2 Network of Excellence, IST-2006-216886, and Project BLANC07-1_184534 of the French ANR.

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