

Minimal Representations of Order Types by Geometric Graphs

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² Charles University, Prague

³ ETH Zürich

⁴ FU Berlin

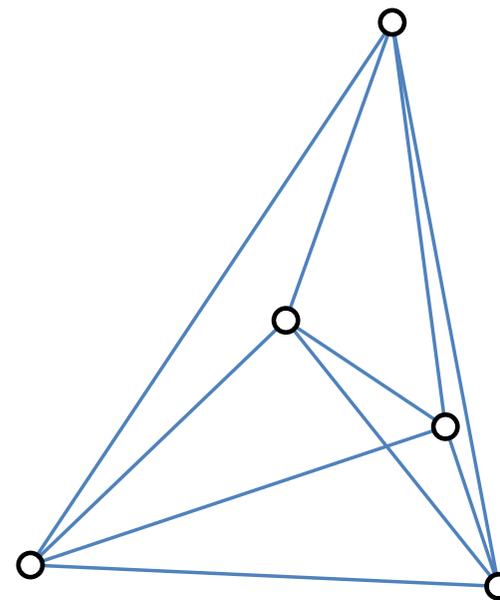
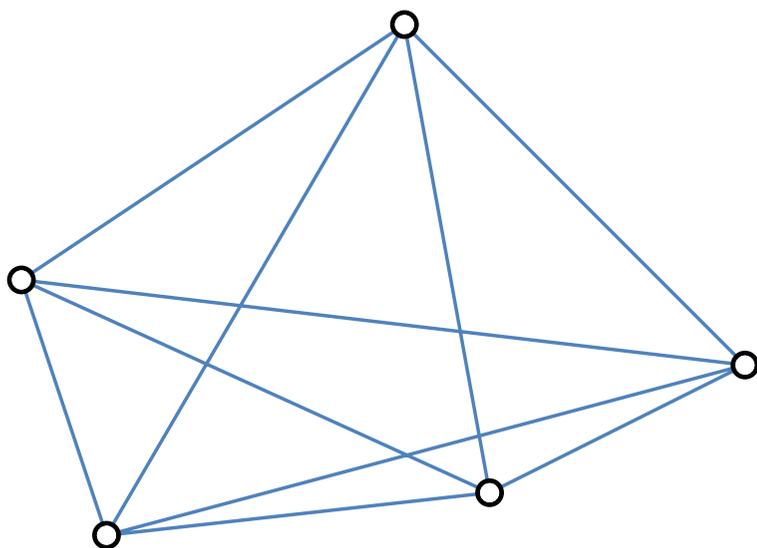
⁵ TU Berlin

Combinatorics of Point Sets

Infinite number of point sets \Rightarrow Finite number classes

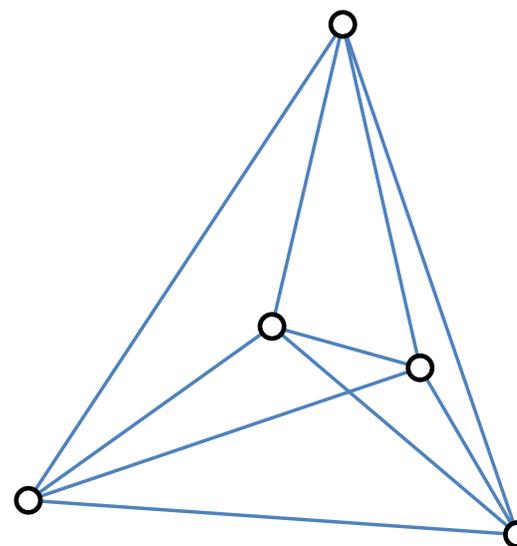
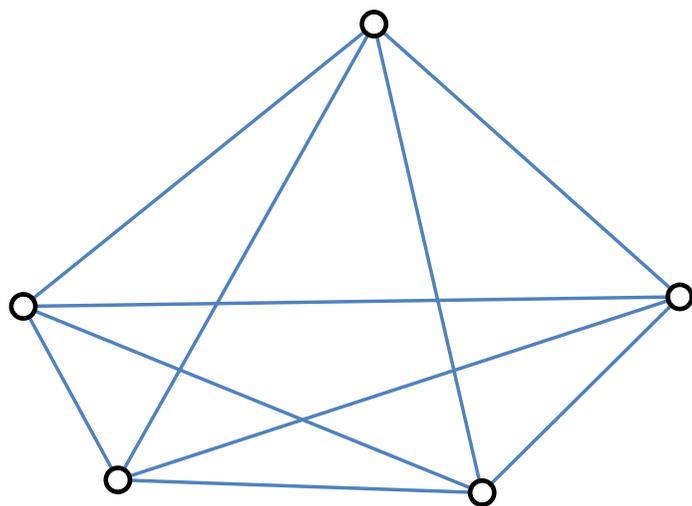
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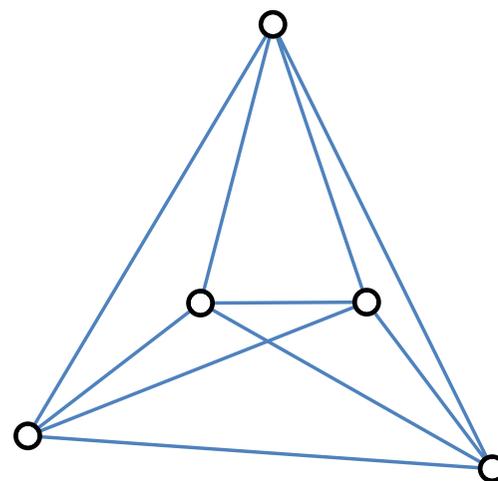
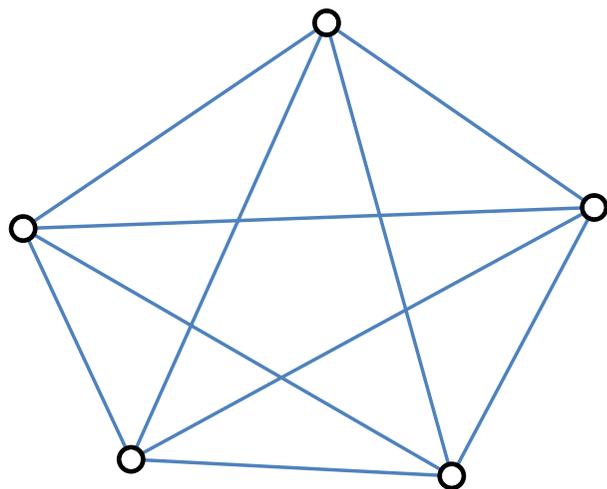
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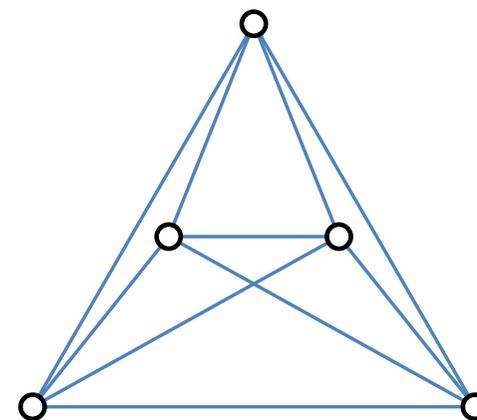
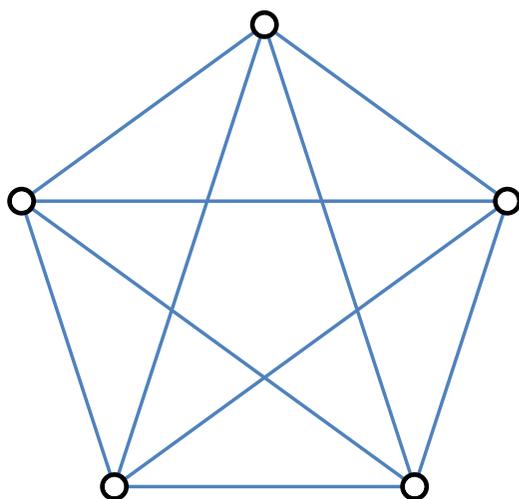
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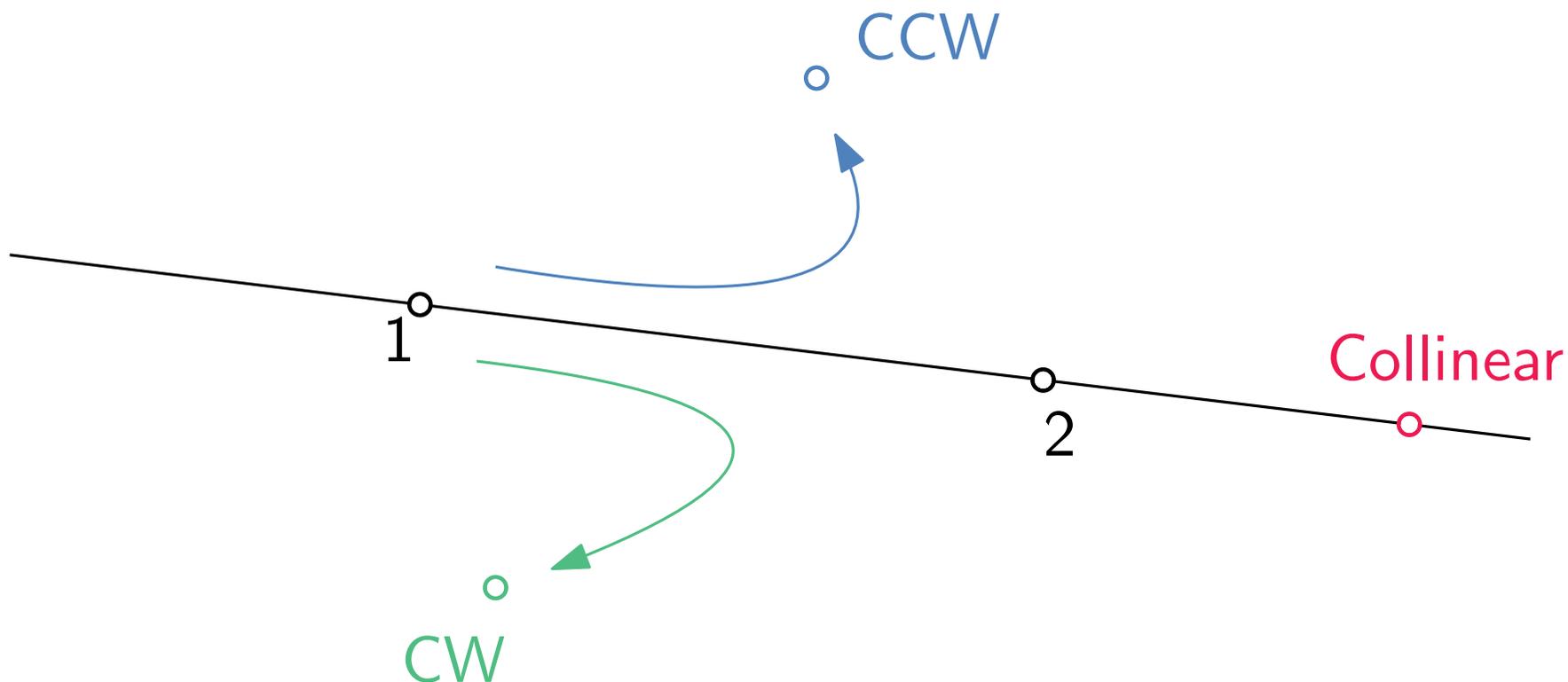
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Order Types

Order types are the equivalence classes of point sets in the plane with respect to their triple-orientations.

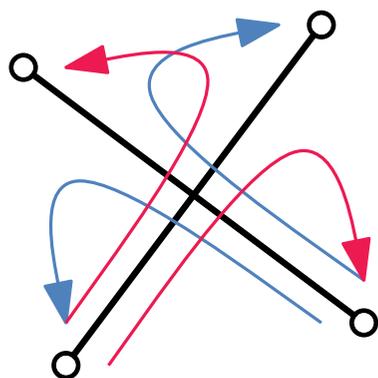
Triple orientations: clockwise, counter clockwise, collinear



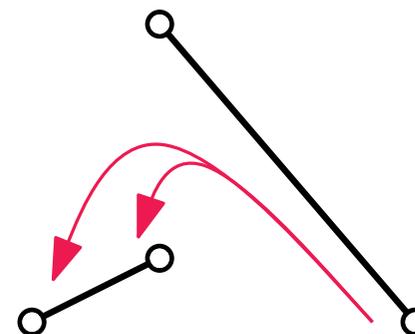
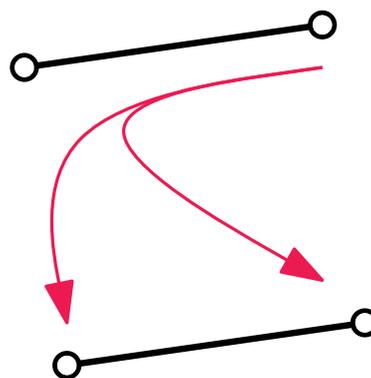
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We can determine whether two edges cross from the triple orientations



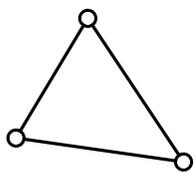
No crossing:



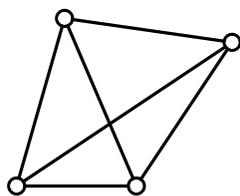
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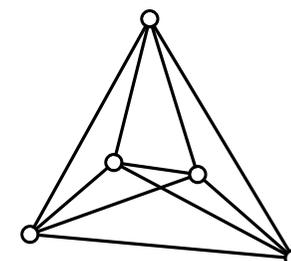
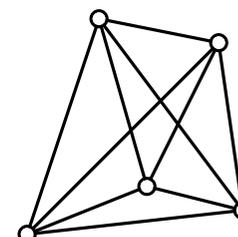
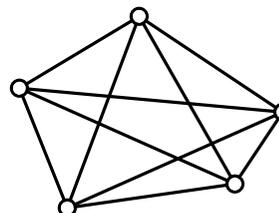
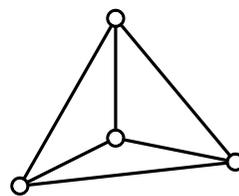
$n = 3$:



$n = 4$:

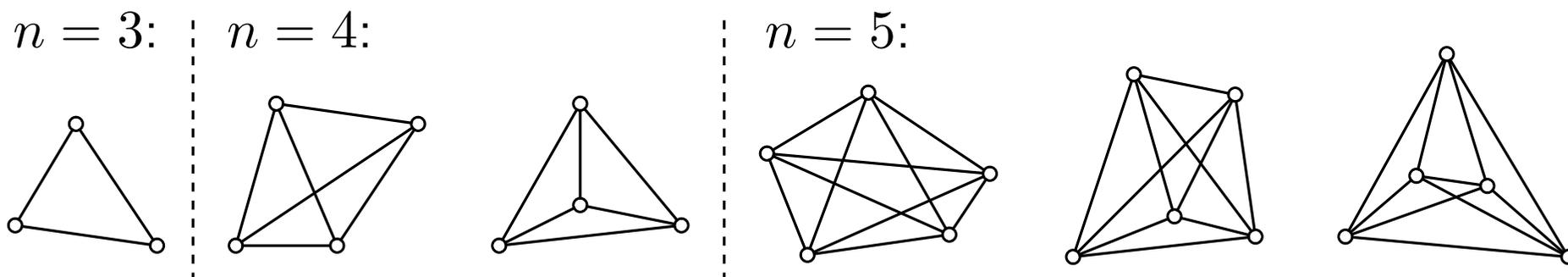


$n = 5$:



Order Types

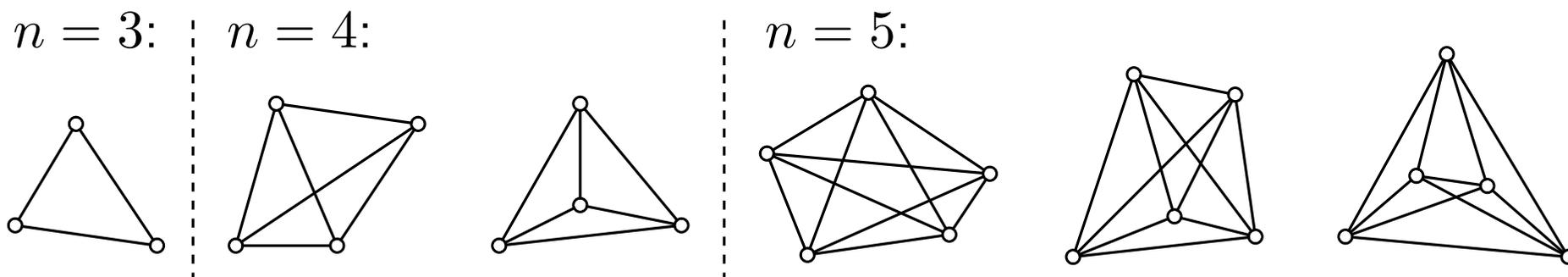
Order types are the equivalence classes of point sets in the plane with respect to their triple-orientations.



n	3	4	5	6	7	8	9	10	11
OT	1	2	3	16	135	3 315	158 817	14 309 547	2 334 512 907

Order Types

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n	3	4	5	6	7	8	9	10	11
OT	1	2	3	16	135	3 315	158 817	14 309 547	2 334 512 907

Nr. of order types: $n^{4n+O(n/\log n)}$ [Goodman & Pollack '86]

Representing Point Sets / Order Types

- Triple orientations

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- Explicit coordinates

0160 7359

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2338 4960

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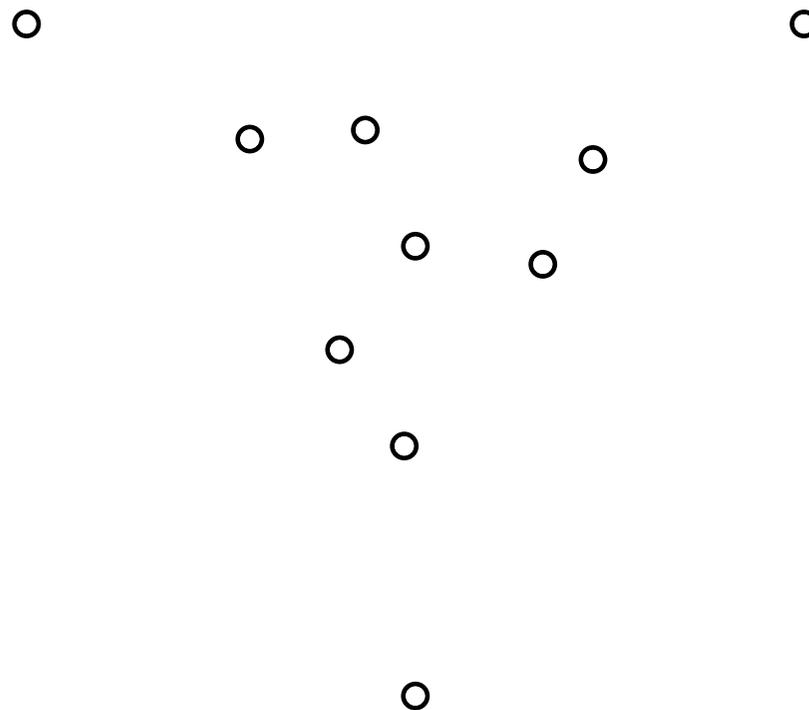
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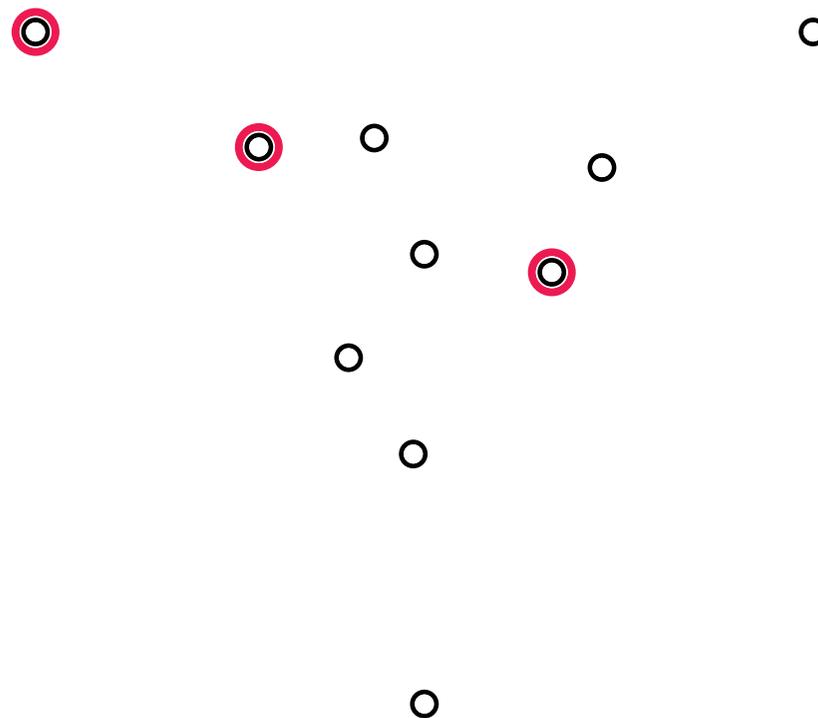
Representing Point Sets / Order Types

- Triple orientations 😞
- Explicit coordinates 😞
- Figure of the point set



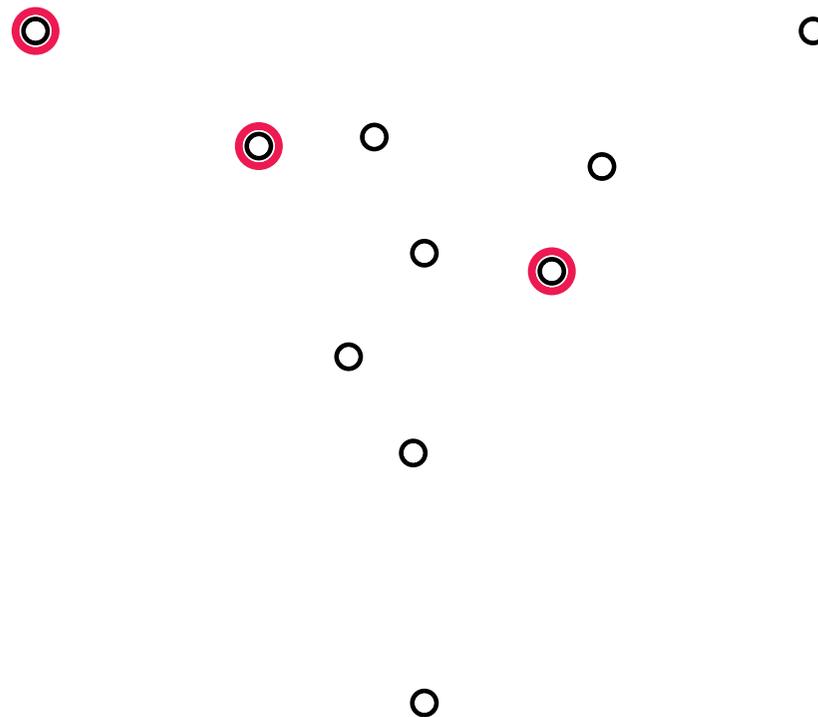
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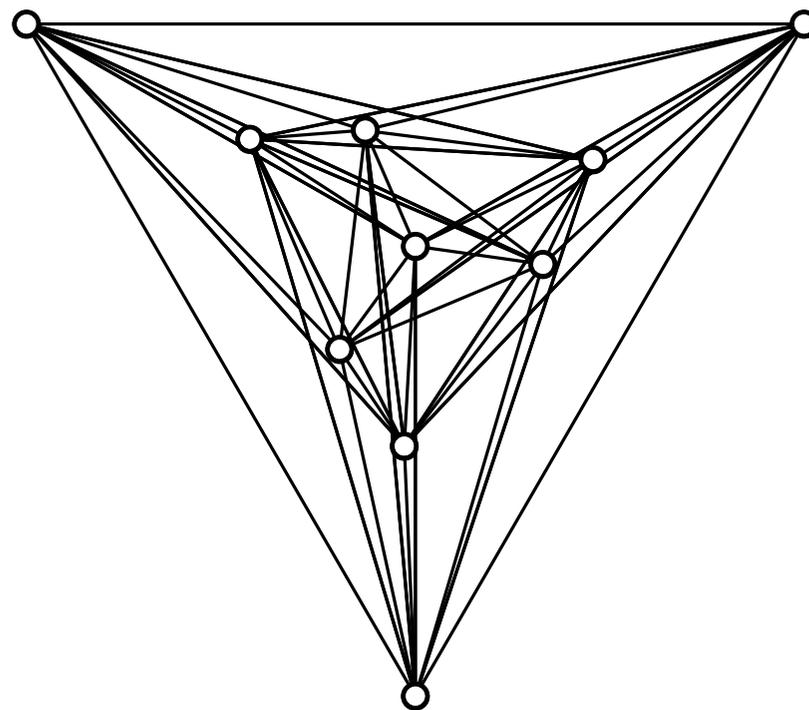
- Triple orientations 🙄
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- Figure of the point set 🤔



Representing Point Sets / Order Types

- Triple orientations 🙄
- Explicit coordinates 🙄
- Figure of the point set 🤔
- + spanned lines/segments

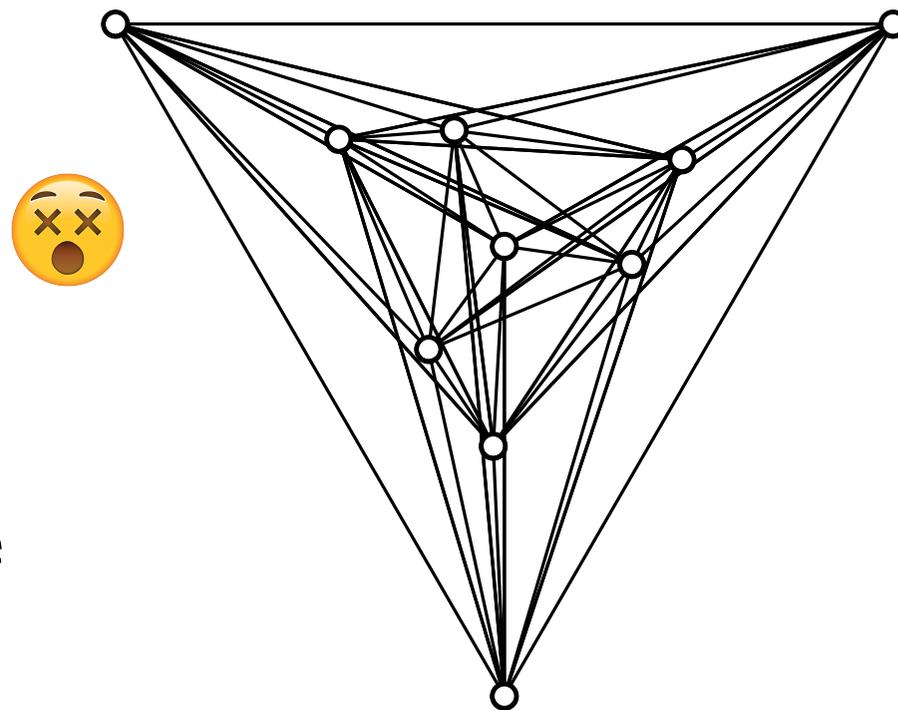
Complete *geometric graph*:
vertices mapped points,
edges drawn as straight-line
segments.



Representing Point Sets / Order Types

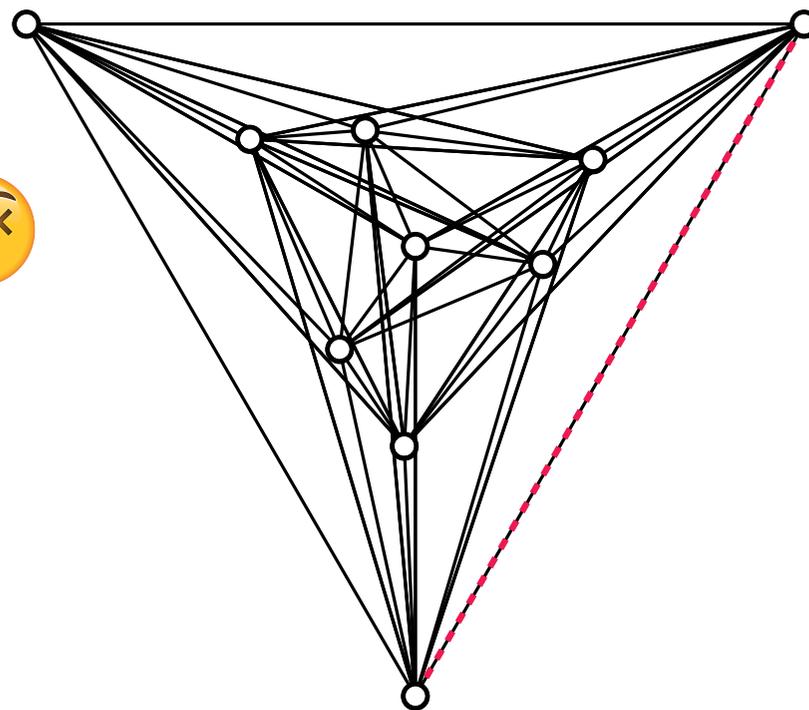
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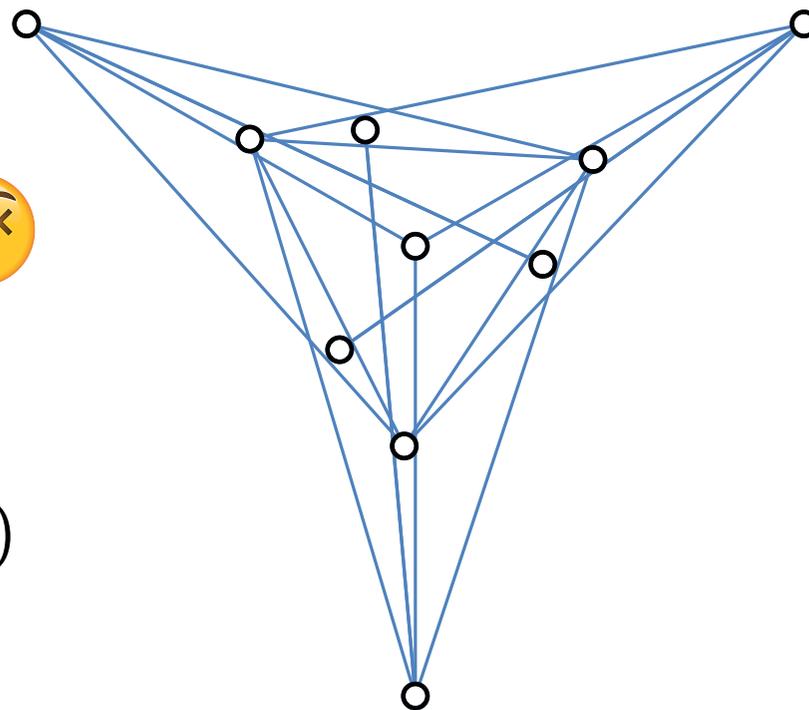
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- + spanned lines/segments 😵
- Points + non-redundant edges



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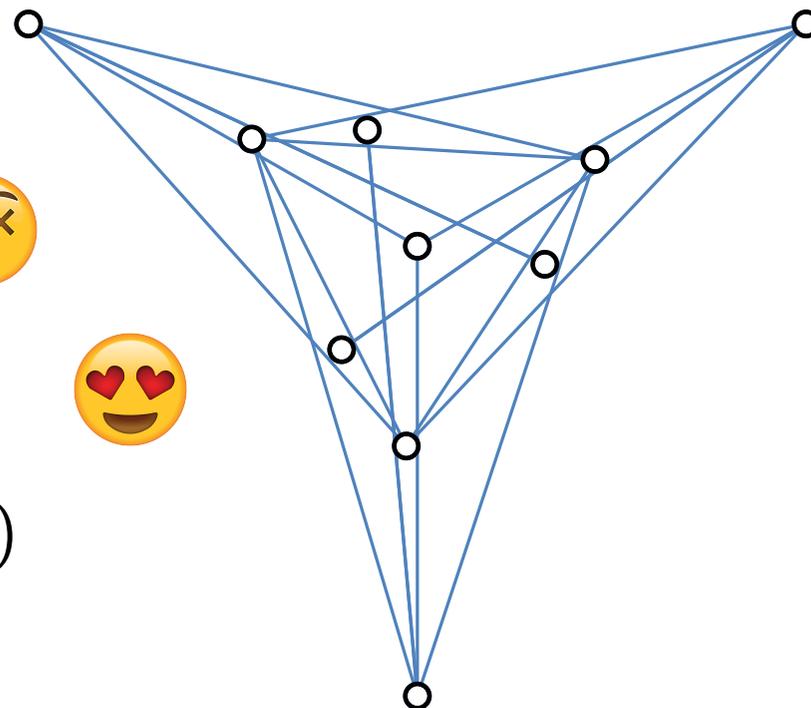
15 edges drawn (total: $45 = \binom{10}{2}$)



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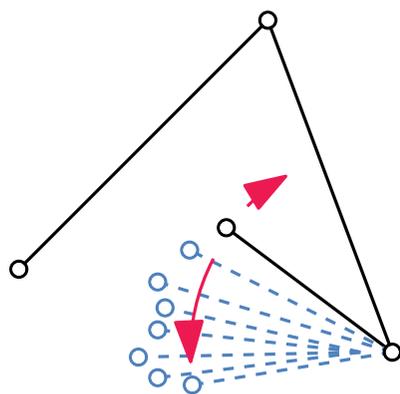


Geometric Graphs Supporting Point Sets

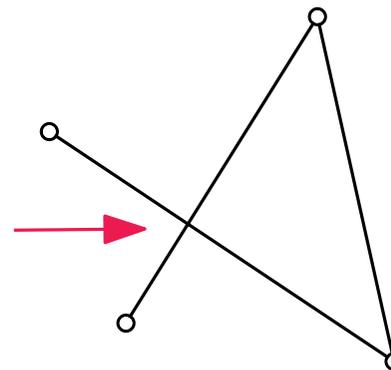
We consider “topology-preserving deformations”.

A geometric graph G *supports* a set S of points if every “continuous deformation” that

- keeps edges straight and
 - allows at most 3 points to be collinear at the same time
- also preserves the order type of the vertex set.



crossing fixed, i.e.,
convex position

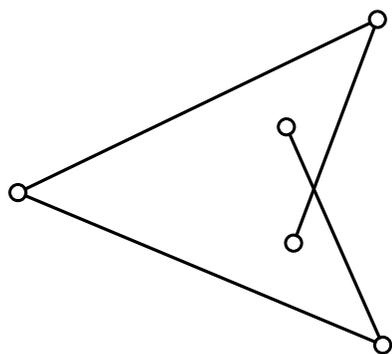


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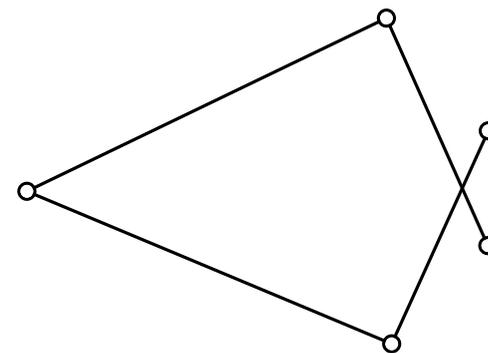
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no such continuous
deformation



Geometric Graphs Supporting Point Sets

We consider “topology-preserving deformations”.

A geometric graph G *supports* a set S of points if every ambient isotopy that

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An *ambient isotopy* of the real plane is a continuous map $f: \mathbb{R}^2 \times [0, 1] \rightarrow \mathbb{R}^2$ such that $f(\cdot, t)$ is homeomorphism for all $t \in [0, 1]$ and $f(\cdot, 0) = Id$.

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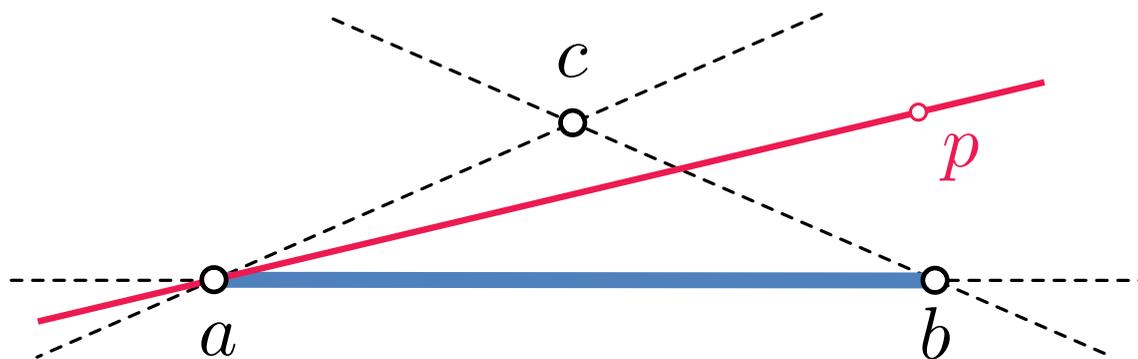
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Every complete geometric graph is supporting.

Exit Edges: Definition

S set of $n \geq 4$ points in general position (no 3 collinear).

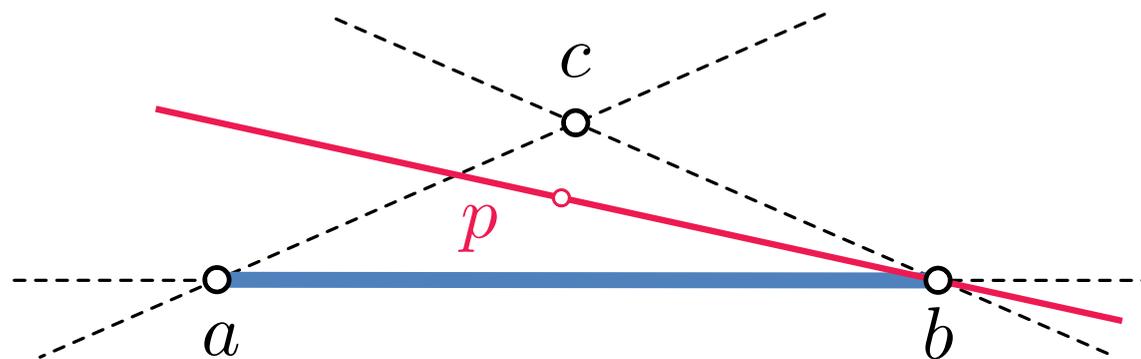
The edge ab is an *exit edge with witness* c if there is no point $p \in S$ such that the line \overline{ap} separates b from c or the line \overline{bp} separates a from c .



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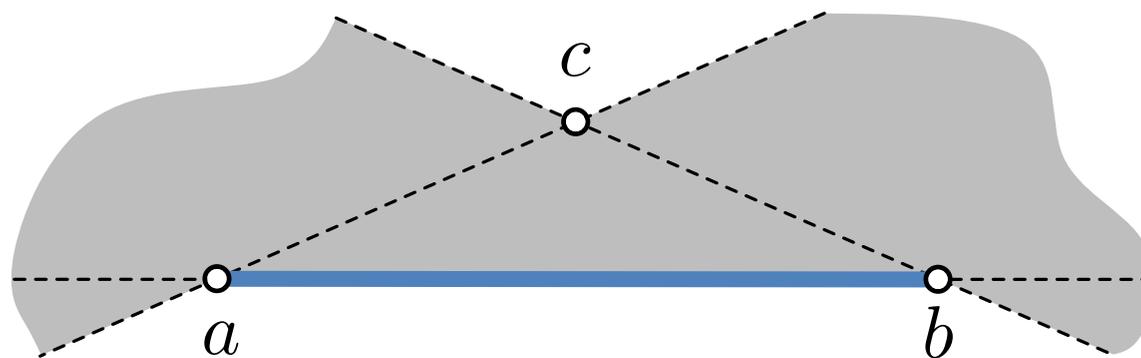
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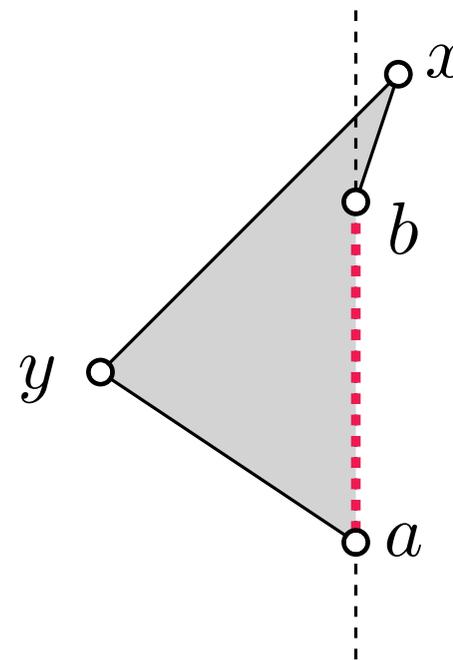
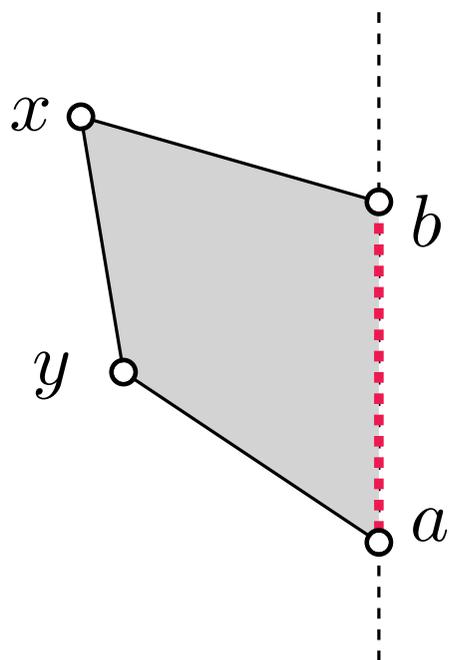
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Exit Edges: Alternative Characterization

The edge ab is not an exit edge if and only if:

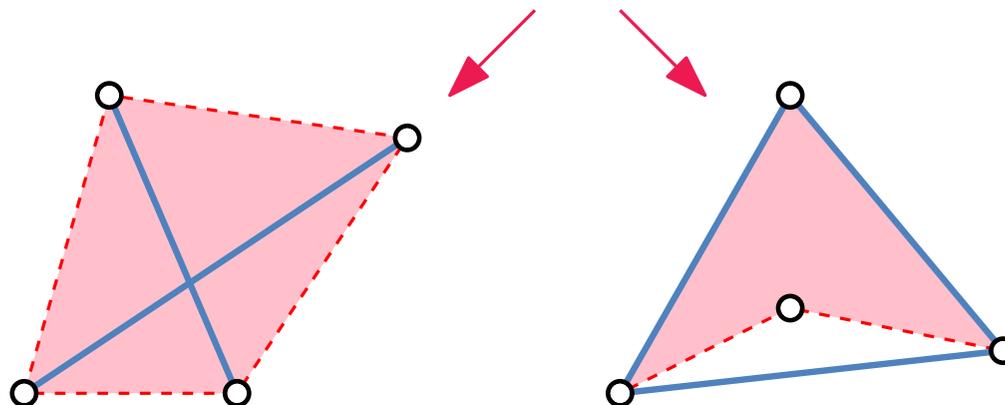
- ab external & incident to convex 4-hole or
- ab internal & incident to general 4-hole on each side, with the reflex angle (if any) incident to ab .



Exit Edges: Small Point Sets

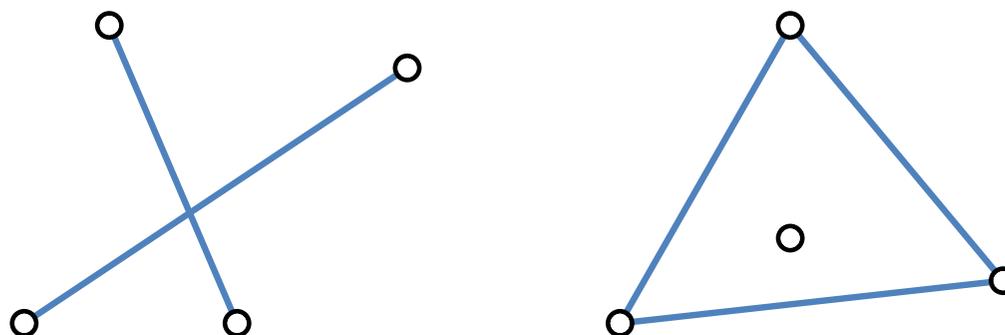
$n = 4$:

classification via 4-holes

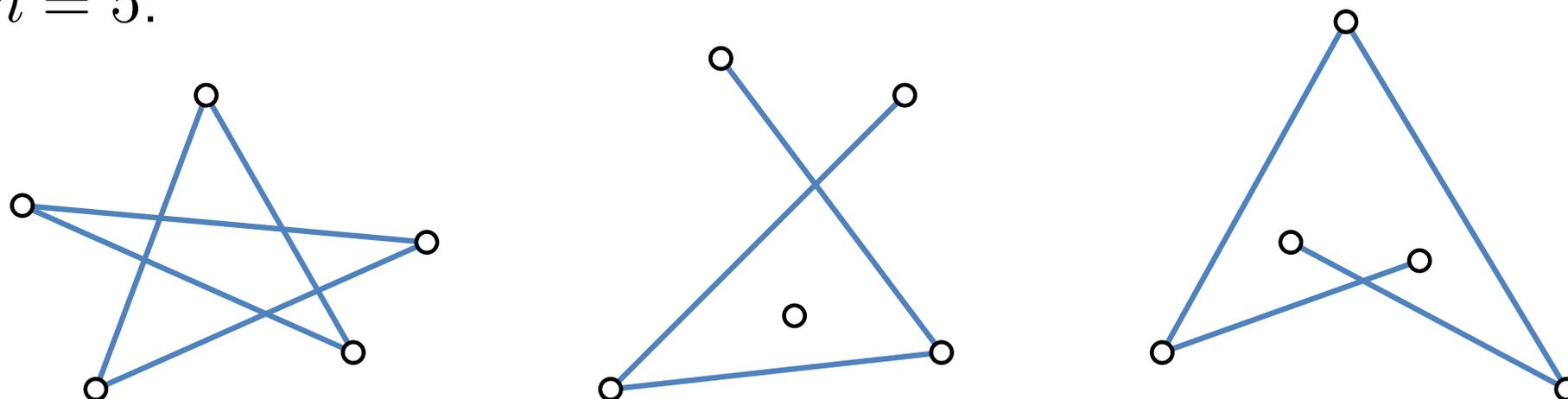


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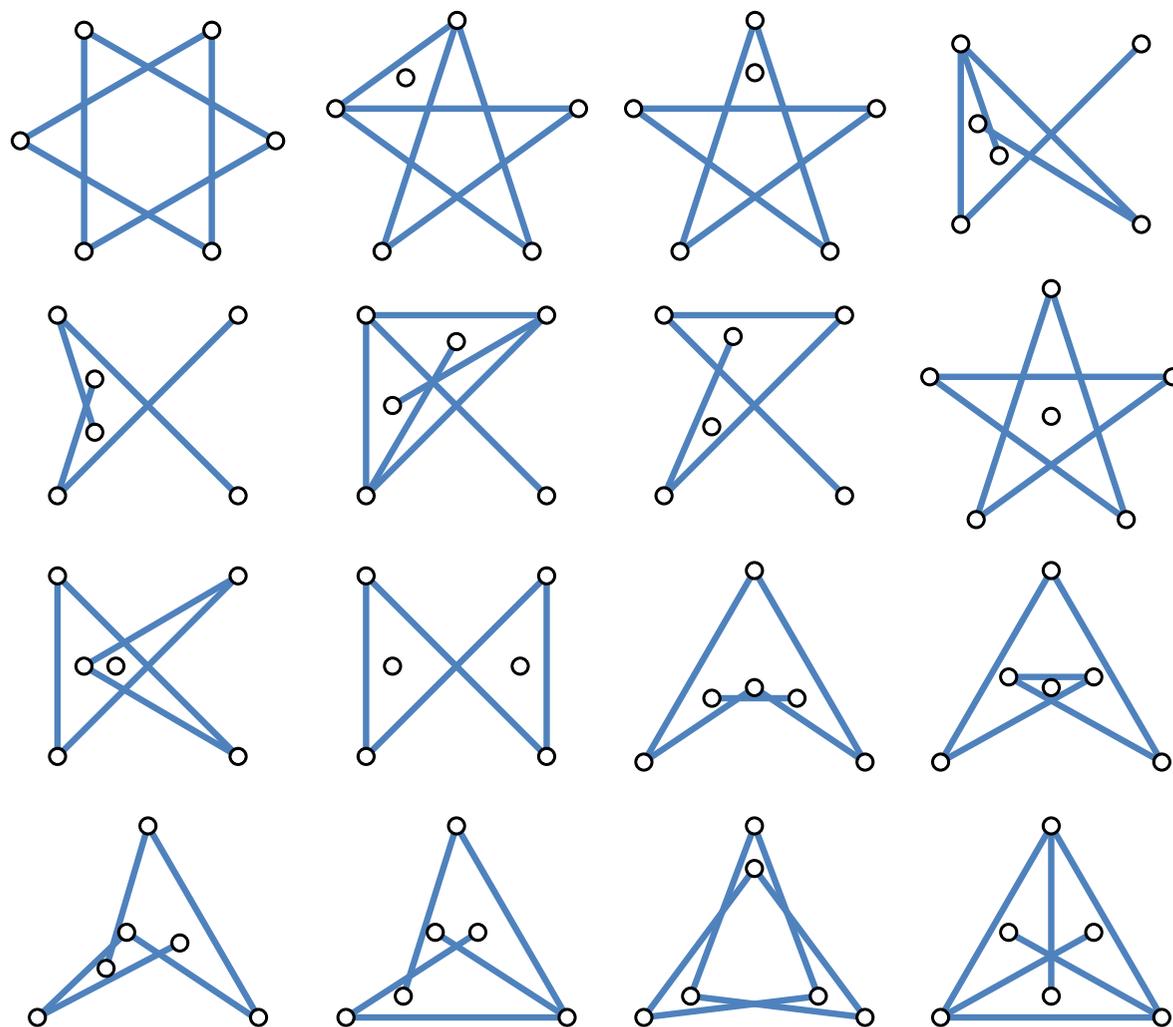


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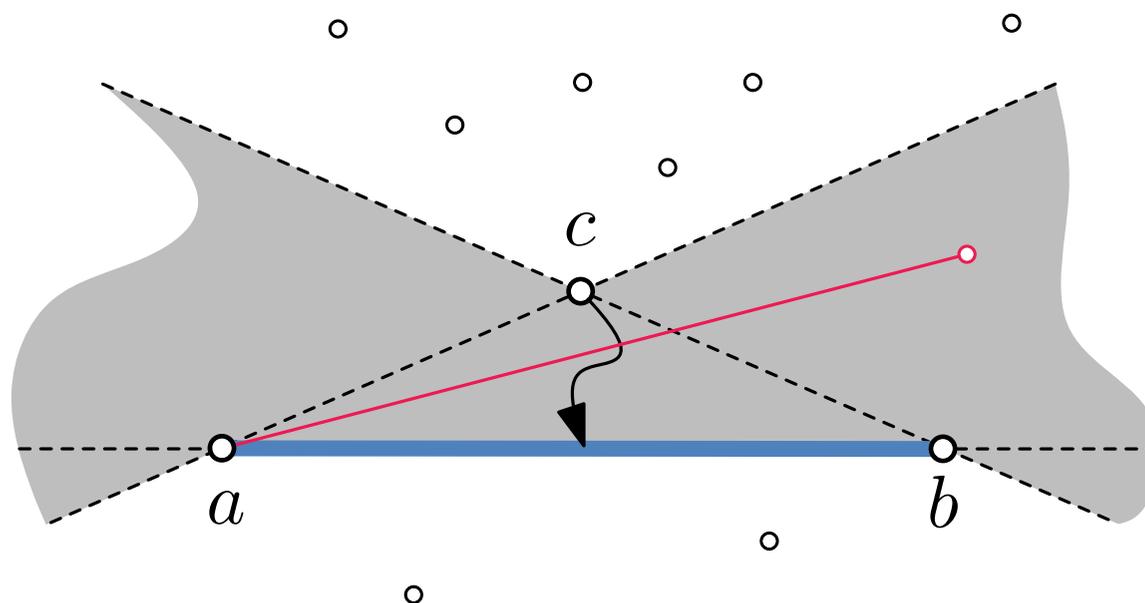
Exit Edges: Small Point Sets

$n = 6$:



Exit Graph Is Supporting

Let $S(t)$ be a continuous deformation of S at time t .
 Let (a, b, c) be the first triple to become collinear, at $t_0 > 0$.
 If c lies on the segment ab in $S(t_0)$,
 then ab is an exit edge in $S(0)$ with witness c .



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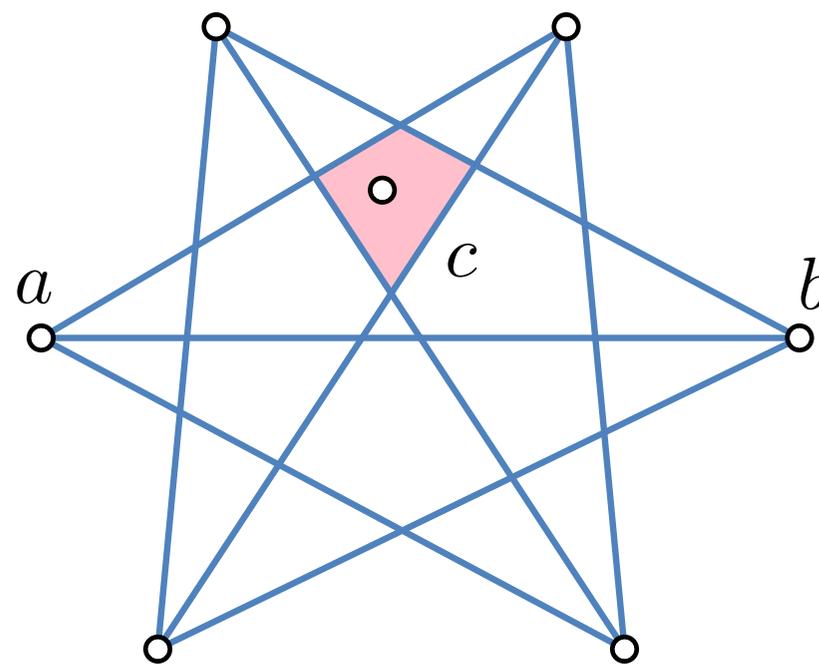
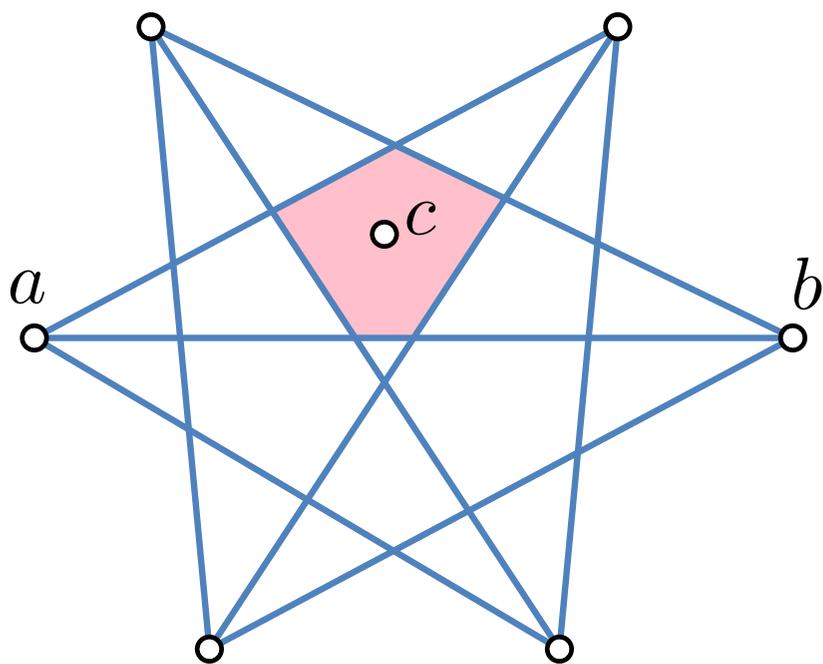
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The graph of exit graph (whose edges are the exit edges) of every point set is supporting.

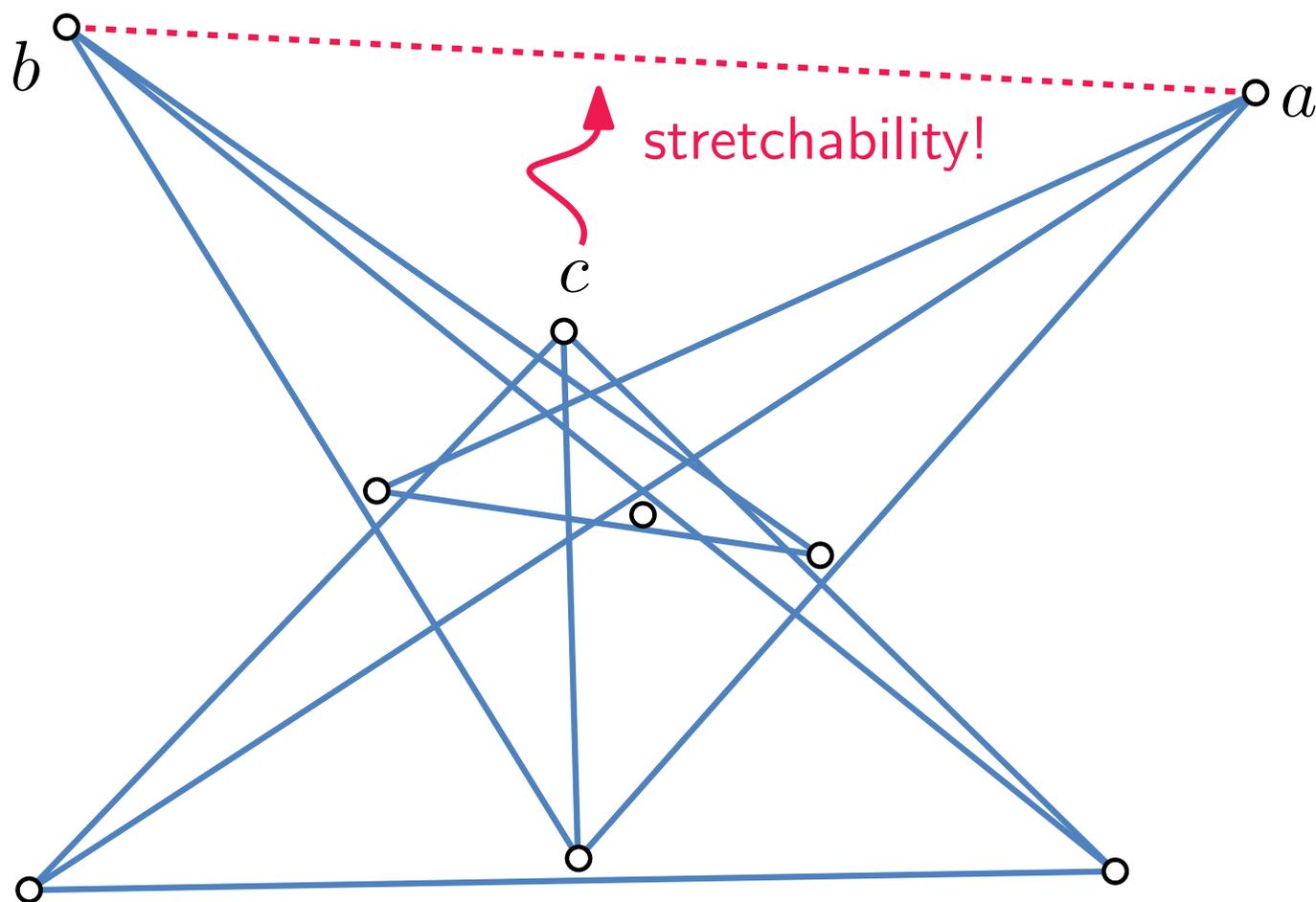
Exit Edges: Observations

It is not always possible to make the witness c reach the corresponding exit edge ab .



Exit Edges: Observations

Exit edges are not necessary in a supporting graph.



Duality

(E.g.) $p = (a, b)$

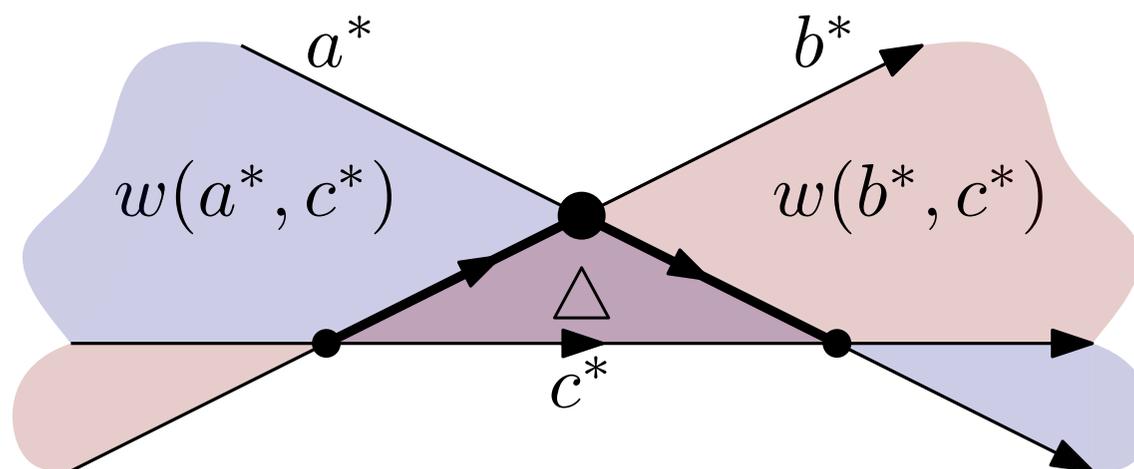


$$p^* := y = ax - b$$

Duality

(E.g.) $p = (a, b) \longrightarrow p^* := y = ax - b$

The edge ab is an exit edge with witness point c in S if and only if the lines a^* , b^* , and c^* bound an unmarked triangular cell in S^* with c^* being the *witness line* and \overline{ab}^* ($= a^* \cap b^*$) being the *exit vertex*.



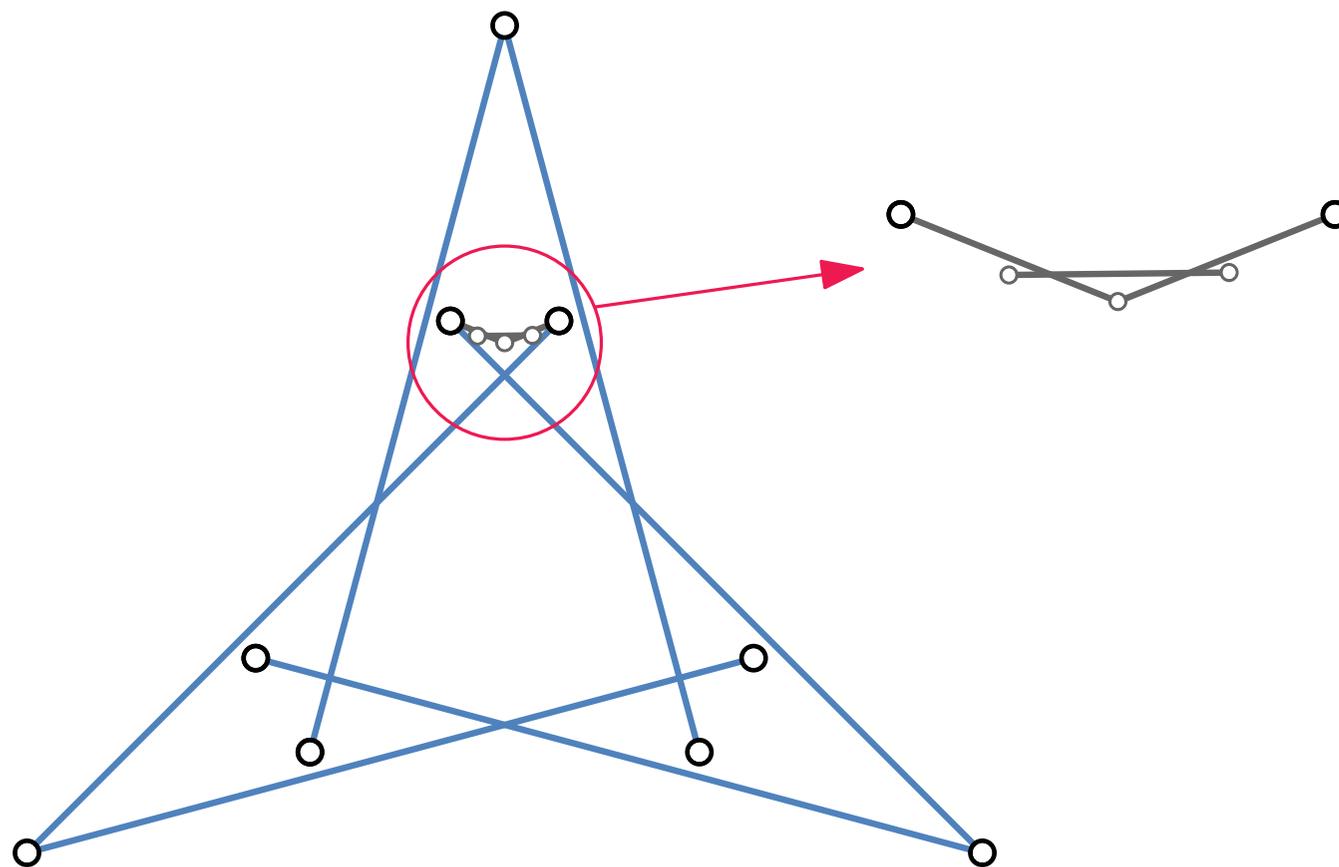
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Lower Bound: There are at least $\frac{3n-7}{5}$ exit edges.

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From the upper bound on the number of triangular cells in line arrangements [Roudneff '72].

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This bound on triangular cells was shown tight for infinitely many values of n [Harborth '85] and [Roudneff '86].

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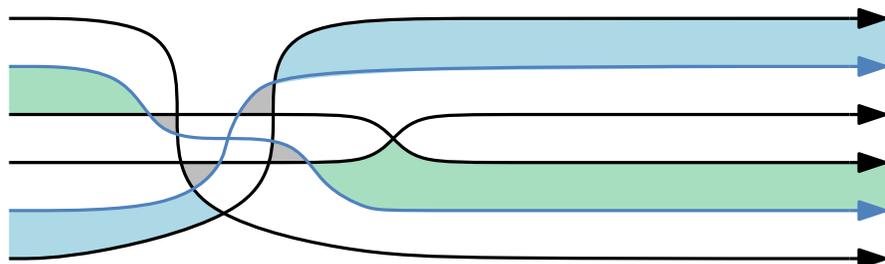
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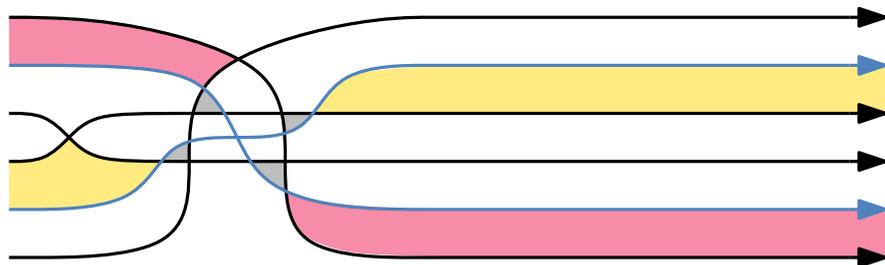
\Rightarrow Construction with $\Theta(n^2)$ exit edges.

Different Order Type, Same Exit Triples

Even if we are given all the exit edges and their witnesses (in the dual, having all triangles and their orientations), we cannot always infer the order type.

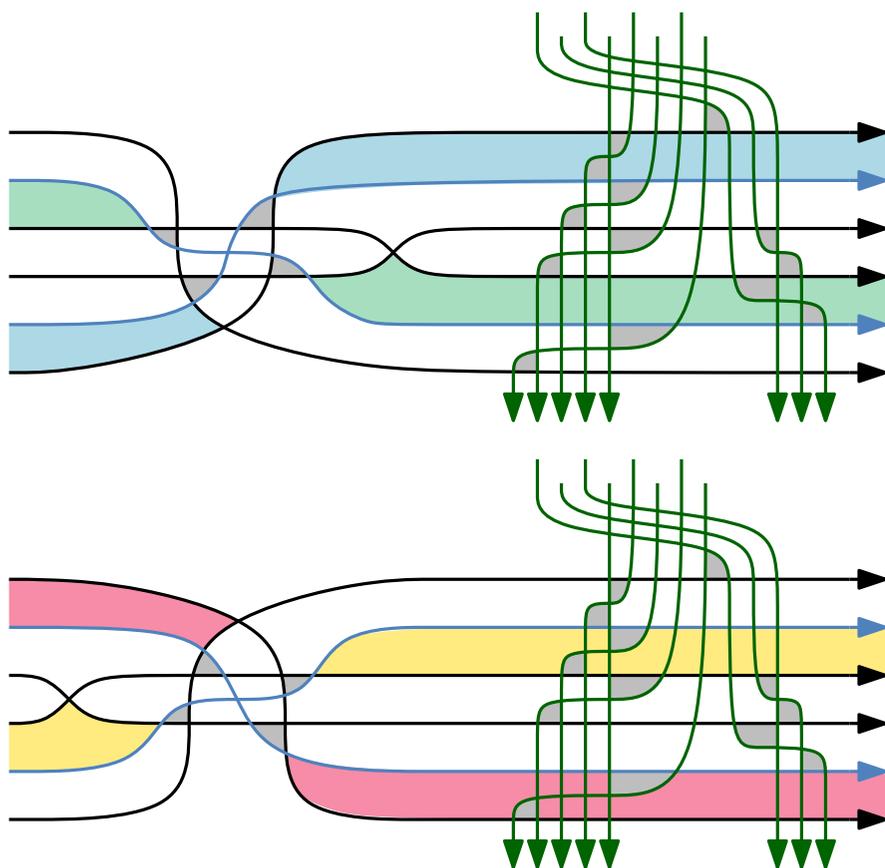


Construction based on an example in [Felsner & Weil '00].



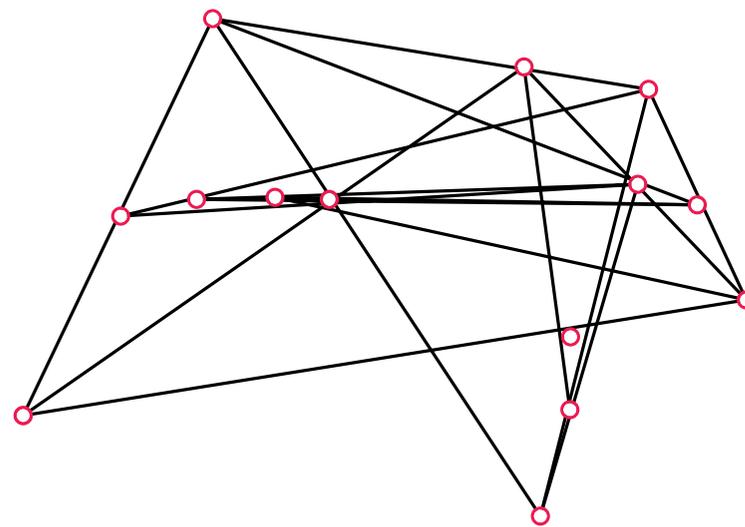
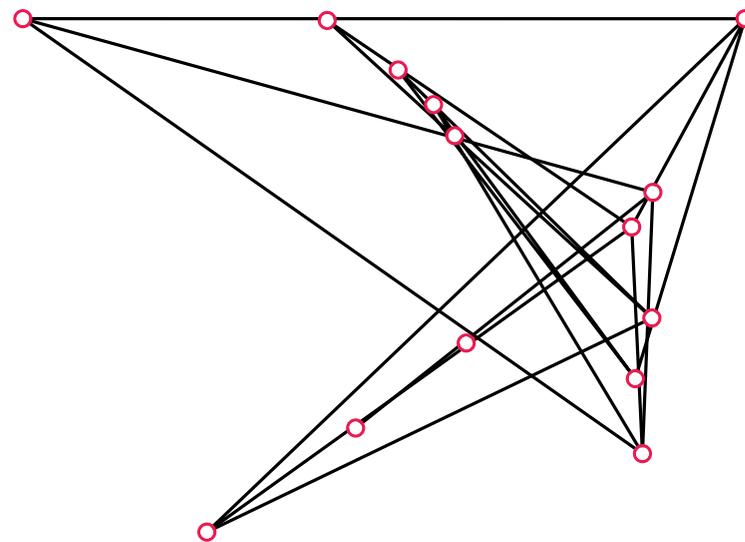
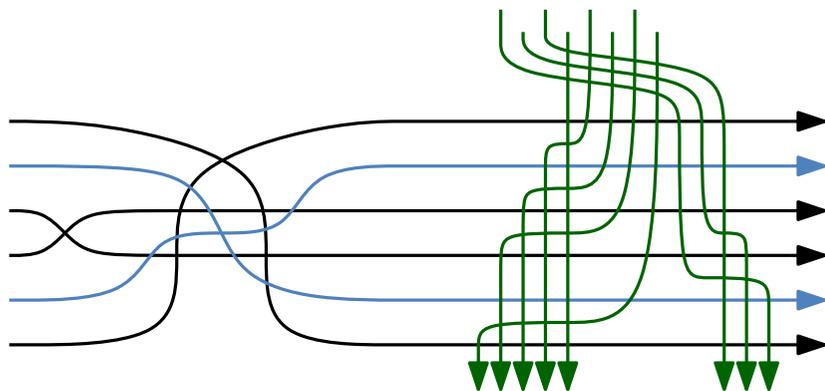
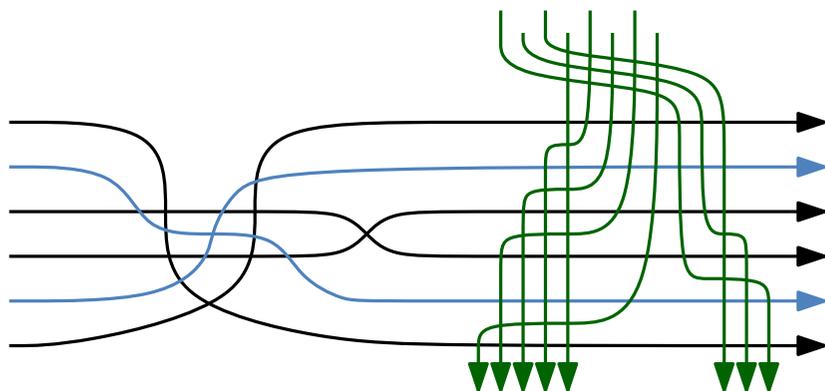
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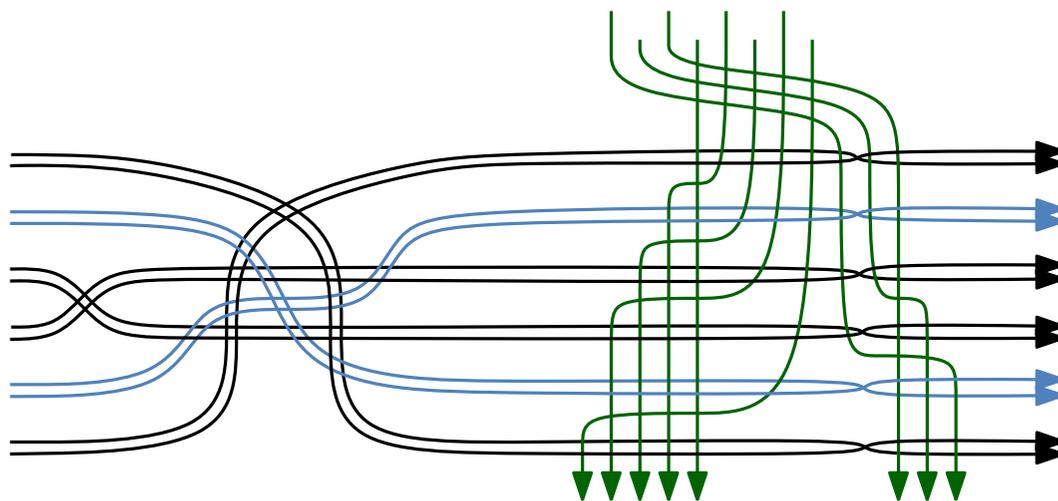
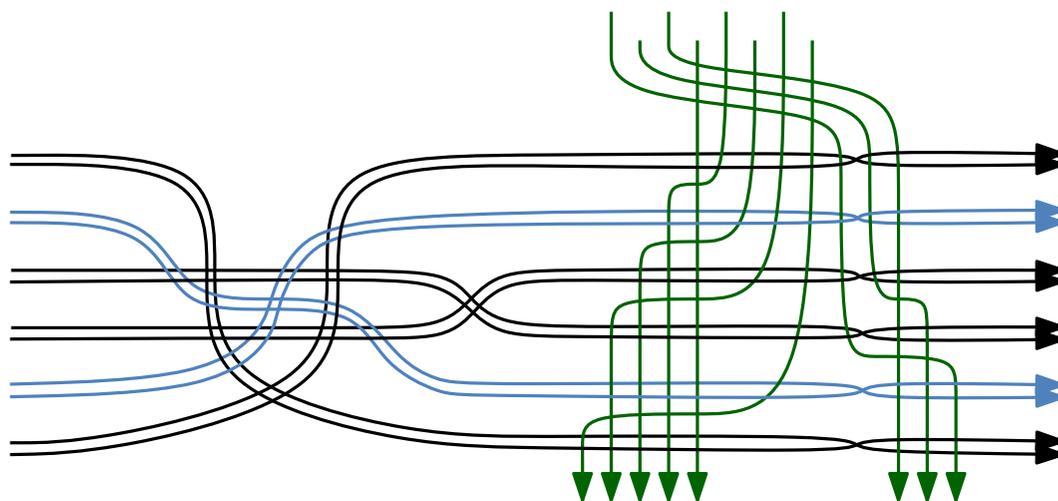


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Conclusions

- Exit edges are useful for representing order types: they are supporting, have a natural dual representation, and can be computed efficiently.
- However, not all of them might be necessary.
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Thank you!