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Critical Placements of a Square or Circle amidst Trajectories for Junction Detection

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Abstract

Motivated by automated junction recognition in tracking data, we study a problem of placing a square or disc of fixed size in an arrangement of lines or line segments in the plane. We let distances among the intersection points of the lines and line segments with the square or circle define a clustering, and study the complexity of *critical* placements for this clustering. Here critical means that arbitrarily small movements of the placement change the clustering.

A parameter ε defines the granularity of the clustering. Without any assumptions on ε , the critical placements have a trivial $\mathcal{O}(n^4)$ upper bound. When the square or circle has unit size and $0 < \varepsilon < 1$ is given, we show a refined $\mathcal{O}(n^2/\varepsilon^2)$ bound, which is tight in the worst case.

We use our combinatorial bounds to design efficient algorithms to compute junctions. As a proof of concept for our algorithms we have a prototype implementation that showcases their application in a basic visualization of a set of n trajectories and their k most important junctions.

1 Introduction

Many analysis problems in geography have an inherent scale component: the “granularity” or “coarseness” at which the data is studied. The most direct way to model spatial scale in geographic problems is by using a fixed-size neighborhood of locations, such as a fixed-size square or circle. For example, *population density* can be studied at the scale of a city or at the scale of a country, where one may consider the population in units with an area of $10^4 m^2$ or $25 km^2$, respectively. There are many other cases where local geographic phenomena are studied at different spatial scales. The Geographical Analysis Machine is an example of a system that supports such analyses on point data sets [10].

In computational geometry, the problem of computing the placement of a square or circle to optimize some measure has received considerable attention. For a set of n points in the plane, one can compute the (fixed-size,

fixed-orientation) square that maximizes the number of points inside in $\mathcal{O}(n \log n)$ time (expand every point to a square, and the problem becomes finding a point in the maximum number of squares which is solved by a sweep). Mount et al. [9] study the overlap function of two simple polygons under translation and show, among other things, that one can compute the placement of a square that maximizes the area of overlap with a simple polygon with n vertices in $\mathcal{O}(n^2)$ time. For a weighted subdivision, one can compute a placement that maximizes the weighted area inside in $\mathcal{O}(n^2)$ time as well [2]; this problem is motivated by clustering in aggregated data. In the context of diagram placement on maps, various other measures to minimize or maximize when placing squares were considered, like the total length of border overlap [16].

Our interest lies in a problem concerning trajectory data. A trajectory is represented by a sequence of points with associated time stamps, and models the movement of an entity through space; we will assume in this paper that the movement space is two-dimensional. The identification of “interesting regions” in the plane defined by a collection of trajectories has been studied in several papers recently. These regions can be characterized as meeting places [4], popular or interesting places [1, 5, 11, 12], and stop regions [8]. In several cases, interesting regions are also defined as squares of fixed size, placed suitably. The more algorithmic papers show such regions of interest can typically be computed in $\mathcal{O}(n^2)$ or $\mathcal{O}(n^3)$ time; what is possible of course depends on the precise definition of the problem. There are many other types of problems that can be formulated with trajectory data. For overviews, see [3, 7].

Besides exact algorithms for optimal square or circle placement, approximation algorithms have been developed for several problems on trajectory and other data, see e.g. [4, 6, 15].

Motivation and problem description. We consider a problem on trajectories related to common movements and changes of movement directions at certain places. Imagine a large open space like a town square, a large entrance hall, or a grass field. People tend to traverse such areas in ways that are not random, and the places where a decision is made and possibly a change of direction is initiated may be specific. Also for data like ant tracks, the identification of places where tracks go differ-

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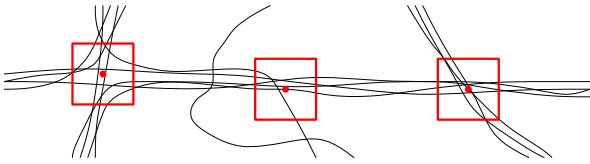


Figure 1: A set of trajectories and square placements at junctions of varying significance.

ent ways is of interest. Without going into details, these observations motivate us to study placements of a square or circle of fixed size such that bundles of incoming and outgoing entities arise.

Consider the tracks in Figure 1. We observe that to define places where the tracks of entities cross and where decisions are made, we can use the placement of a square of a certain size and where the tracks enter and leave the square. We are interested in placements that give rise to bundles: large subsets of tracks that enter and leave the square at a similar place on its boundary, and with a gap to the next location along the boundary where this happens. The left square in the figure has five bundles where one bundle consists of only one trajectory, and the middle and right square have only two bundles (albeit with different “topology”). We see that the left and right squares indicate regions that should be considered more significant than the middle one for being a junction. The main difference between the left and right junctions is that on the left, decisions are made to go straight or change direction, whereas on the right, all moving entities went straight and no different decisions were taken.

We study an abstracted version of this placement problem and ignore many of the practical issues that our simplified definition of a junction would have. Later in the paper we briefly address such issues by giving a slightly more involved definition of a junction. The majority of the paper concentrates on an abstract combinatorial and computational problem that lies at the core of junction detection.

Let \mathcal{T} be a collection of trajectories, let \square_p be the boundary of a unit square S centered at p placed axis-aligned amidst the trajectories, and let ε be a positive real constant. Let $Q = \mathcal{T} \cap \square_p$ be the set of all intersections of trajectories with the boundary of the square (here we can ignore the time component of trajectories; they are considered polygonal lines). Two points in Q are ε -close if their distance along \square_p is at most ε . \mathcal{T} and \square_p give rise to a *clustering* of Q on \square_p by the transitive closure relation of ε -closeness. Different clusters are separated by a distance larger than ε along \square_p . A single cluster of Q corresponds to parts of trajectories that enter or leave S in each other’s proximity (in Figure 1 from left to right the squares define four, three, and four

clusters respectively).

Now consider the two-dimensional space of all placements of a square of fixed size by choosing its center as its reference point. We say that a placement q is *critical*, if any arbitrarily small neighborhood of q contains points inducing different clusters. This can be due to a change in size of a cluster on \square_q or to a change in the clustering. The latter corresponds to placements where the distance between two points of $\mathcal{T} \cap \square_p$ on \square_p is exactly ε , with no other points of $\mathcal{T} \cap \square_p$ in between. Since noncritical points are part of a region that defines the same clustering, one can think of the set of critical points to be the boundary between these regions.

Results and organization. In Section 2 we analyze the complexity of the space of critical placements for fixed-size squares in an arrangement of n lines. We show that the placement space has $\mathcal{O}(n^2/\varepsilon^2)$ total complexity in the worst case, and can be constructed in $\mathcal{O}(n^2 \log n + k)$ time where k is the true complexity (the latter appearing in the full version [14] due to space constraints). In Section 4, we show that these results are tight by presenting an explicit construction that exhibits the worst-case behavior. In Section 5 we discuss our application to junction detection further and show output from a prototype implementation. We conclude in Section 6. In the full version of the paper [14] we further show how to extend our approach to more realistic settings, such as placing a square on an arrangement of line segments or placing a circle rather than a square.

2 Square on lines

We begin by studying the simplest version of the problem: placing a unit square over an arrangement of lines. The lines “cut” the boundary of the square into several pieces. We are interested in all placements of the square such that one of these pieces has length exactly ε , in which case we call the piece an ε -segment and the placement *critical*. When a piece contains one of the corners of the square, its length is the sum of its two incident line segments. Note that this definition of a critical placement is a simplification of the one defined earlier in terms of clusters; it only considers merging and splitting clusters. In the definition from the introduction, a placement is also critical if a corner of the square coincides with a line. However, these placements are simply four translates of the input lines, so the rest of this section focuses on the harder critical placements as defined here.

2.1 Placement space

Let \mathcal{L} be a set of lines and denote by \mathcal{A} the arrangement of \mathcal{L} . For a placement of the square on \mathcal{A} , consider all cells that contain part of its boundary. To characterize all critical placements, we look at how the square can

be “moved around” such that a given cell of \mathcal{A} contains an ε -segment throughout the motion. For instance, in Figure 2 on the left, we can move the square slightly left and right such that there is always an ε -segment in the same cell. We use the intuition of moving the square to argue that the critical placements can be characterized as a set of line segments, and then prove an upper bound on how many times these line segments can intersect.

Definition 1 Let \mathcal{L} be a set of lines and \square_p be the boundary of an axis-aligned unit square whose center is denoted by p , and let $\varepsilon > 0$ be a constant. A placement of \square_p (or p) is an ε -placement if at least one connected component in $\square_p \setminus \mathcal{L}$ has length exactly ε . An ε -segment is a connected component of $\square_p \setminus \mathcal{L}$ with length exactly ε .

Consider the example from the figure again. When moving p to the right we maintain the indicated ε -segment; this reduces p 's movement to one degree of freedom. It can happen that when moving p , another ε -segment is created in another cell. This means that this ε -placement gives rise to two ε -segments. We assume \mathcal{L} to be in general position such that no two ε -segments give p the same allowed movement (a condition that is met after perturbing the input). Therefore no more than two ε -segments will ever occur simultaneously.

Since ε -segments are part of \square_p , it is convenient to fix a point p' on \square_p and look at the movement of p' instead of p . Thus, by moving the square such that an ε -segment is maintained inside a cell c in \mathcal{A} , the point p' traces a curve. If we consider only those parts of this curve corresponding to placements where p' lies on the ε -segment, we observe that this subcurve is contained in c . For instance, in Figure 2 on the bottom right, the fixed point p' can be moved vertically (p and the square move accordingly) exactly between the intersection points with \mathcal{L} . To facilitate our analysis, we will choose a set of fixed points on \square_p such that any ε -segment will contain exactly one of these points. For ease of presentation we assume that $\frac{1}{\varepsilon}$ is integer, so that we can place exactly $\frac{1}{\varepsilon}$ fixed points with distance ε apart along \square_p . If it is not integer, we can pick fixed points such that an ε -segment contains one or two fixed points, in which case our analysis overcounts by a constant factor.

Since these points are fixed with respect to p , we define them in terms of *translation vectors*. We write $\tau(X)$ for the translation by τ of any object X . The inverse of τ is denoted τ^{-1} . Thus, in Figure 2, $p' = \tau(p)$.

Definition 2 Let $\frac{1}{\varepsilon}$ be integer. T_ε is the set of $\frac{1}{\varepsilon}$ vectors such that $\square_p \setminus \{\tau(p) \mid \tau \in T_\varepsilon\}$ is a set of open line segments each of length ε , and T_ε includes all vectors σ such that $\sigma(p)$ is a corner of \square_p .

Let c be a cell of \mathcal{A} and $\tau \in T_\varepsilon$ a vector. We denote by $S(c, \tau)$ the set of all critical placements p such that

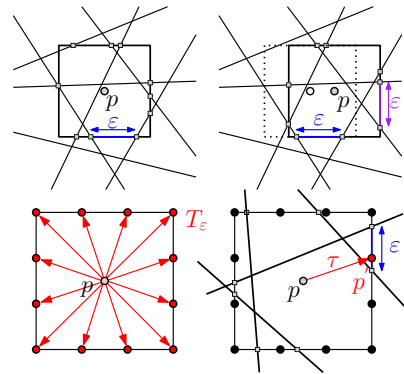


Figure 2: Top: placement of square with one ε -segment (Left) and two ε -segments (Right). Bottom: the set of vectors T_ε (Left) and an ε -placement p with the vector in T_p indicated (Right).

$\tau(p)$ lies on an ε -segment in c . That is, $\tau(S(c, \tau))$ is the set of curves traced out by $\tau(p)$ under our previous interpretation of moving p' . We note that some cells are “too small” to contain an ε -segment, in which case $S(c, \tau)$ is empty; other cells may contain up to two disconnected curves (see Figure 3). As shorthand notation, let $S(\tau)$ denote the union of all $S(c, \tau)$ over all cells in \mathcal{A} .

If $\tau(p)$ is not a corner of \square_p , then $\tau(S(c, \tau))$ coincides with (one¹ or) two parallel axis-aligned ε -segments contained in c . Therefore, the number of such segments is bounded by twice the number of cells in the arrangement of lines. If $\tau(p)$ is a corner of \square_p , the shape of $S(c, \tau)$ is more complex. This means that a similar bound on $S(\tau)$ as before is not as easy to achieve. Figure 3 shows the construction of $S(c, \tau)$ when $\tau(p)$ is the upper right corner of \square_p . The curve inside c shows exactly how $\tau(p)$ can be moved such that c contains an ε -segment containing $\tau(p)$. Translated by the inverse of τ , we get the actual ε -placements of p corresponding to the particular cell c and vector τ . Note that the figure also shows the only case when $S(c, \tau)$ can be disconnected, i.e. when c contains an acute angle in the same “direction” as τ . We will show that for the four corner vectors τ , the curves in $S(\tau)$ have properties that allow us to bound the complexity of the space of all ε -placements.

Lemma 1 For $\tau \in T_\varepsilon$ and a cell c in \mathcal{A} , $S(c, \tau)$ consists of at most two connected subsets of a piecewise linear and convex curve.

Proof. If $\tau(p)$ is not a corner point of \square_p then $S(c, \tau)$ is either empty or consists of two single line segments.

Without loss of generality let τ translate p to the upper right corner of \square_p . Because the result must hold for arbitrary ε , we define the following function f related to

¹Degenerate case where the width or height of c is exactly ε .

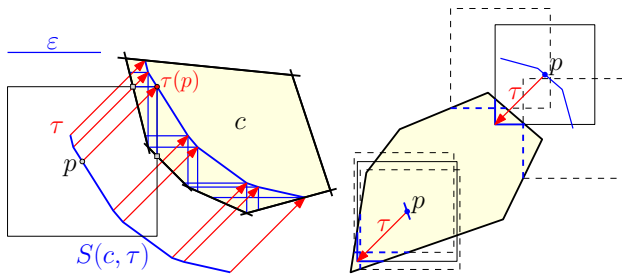


Figure 3: Left: construction of the curve $S(c, \tau)$. Right: $S(c, \tau)$ can consist of multiple pieces.

the notion of an ε -segment, but without being dependent on ε .

For a point a , let x_a be the distance to the closest line in \mathcal{L} left of a , and let y_a be the distance to the closest line below a ; define $f(a) = x_a + y_a$. Let f_c be f restricted to the points in a cell c of \mathcal{A} , and consider two points a and b inside c . For a point v halfway between a and b , we have $x_v \geq (x_a + x_b)/2$ and $y_v \geq (y_a + y_b)/2$ by the convexity of c . It follows that $f_c(v) \geq (f_c(a) + f_c(b))/2$. Thus, f_c is a concave function inside c , and taking the level set of a concave function yields a convex curve (possibly extending outside c). Observe that the set of all points $a \in c$ such that $f(a) = \varepsilon$ is the same as $S(c, \tau)$ and is a level set of f_c , so it is convex. Similarly, f_c is piecewise linear and hence, so is $S(c, \tau)$. Since there are at most 4 points on the boundary of c where f_c has value ε , $S(c, \tau)$ consists of at most two connected components. \square

2.2 Complexity

Lemma 2 For all $\tau \in T_\varepsilon$, $S(\tau)$ consists of $\mathcal{O}(n^2)$ line segments.

Proof. For any τ not corresponding to a corner, $S(\tau)$ contains at most two horizontal or two vertical line segments for each cell of \mathcal{A} . Next, assume that τ corresponds to a corner of \square_p , say, the upper right corner. Let c be a cell with k edges in \mathcal{A} , and let p be an ε -placement such that $\tau(p) \in c$. For a fixed y -coordinate of p , there are at most two ε -placements with $\tau(p) \in c$ by convexity of the cell c . Furthermore, for each vertex of $S(c, \tau)$, the point $\tau(p)$ aligns horizontally or vertically with a vertex of c . It follows that the complexity of $S(c, \tau)$ is $\mathcal{O}(k)$. Summing over the complexities of all cells in the arrangement gives the bound. \square

We are interested in the complexity of the placement space of \square_p , and it is therefore important to know how many times two sets of curves $S(\tau)$ and $S(\sigma)$ intersect, for $\tau, \sigma \in T_\varepsilon$. An intersection of these two sets corresponds to a placement of \square_p such that $\tau(p)$ and $\sigma(p)$ both lie on an ε -segment of \square_p . The following lemma

shows that the number of intersections is bounded by the complexity of \mathcal{A} .

Lemma 3 For distinct $\tau, \sigma \in T_\varepsilon$, the intersection of $S(\tau)$ and $S(\sigma)$ contains $\mathcal{O}(n^2)$ points.

Proof. Let p be an ε -placement such that $p \in S(\tau) \cap S(\sigma)$, for distinct $\tau, \sigma \in T_\varepsilon$. Let $\mathcal{A}' = \mathcal{A}(\tau^{-1}(\mathcal{L}) \cup \sigma^{-1}(\mathcal{L}))$ be the arrangement of two copies of \mathcal{L} translated by the inverses of τ and σ . Let c denote the cell in \mathcal{A}' that contains p , and let c_τ and c_σ denote the cells in \mathcal{A} that respectively contain $\tau(p)$ and $\sigma(p)$ (see Figure 4). Observe that $c = \tau^{-1}(c_\tau) \cap \sigma^{-1}(c_\sigma)$.

Let $s(\tau)$ denote the line segment in $S(c_\tau, \tau)$ on which p lies. Distinguish the following two cases for p : either at least one end point of $s(\tau)$ or $s(\sigma)$ lies in c , or none. In the first case, without loss of generality assume that one end point of $s(\tau)$ lies in c . By Lemma 1, $S(c_\sigma, \sigma)$ consists of at most two convex curves, hence $s(\tau)$ intersects $S(c_\sigma, \sigma)$ at most four times. Because $S(c_\sigma, \sigma)$ is the only part of $S(\sigma)$ intersecting c , it also holds that the part of $s(\tau)$ inside c intersects $S(\sigma)$ only four times. Thus, all intersections of this kind are bounded by the number of vertices in $S(\tau)$, which by Lemma 2 is $\mathcal{O}(n^2)$.

In the other case, no end point of $s(\tau)$ or $s(\sigma)$ lies in c . Consider an edge e of c in \mathcal{A}' that intersects $s(\tau)$. Since e intersects $s(\tau)$ it must be an edge of c_σ . Therefore, it intersects $S(c_\tau, \tau)$ and thus $S(\tau)$ at most twice.

Therefore, the number of intersections of this kind is bounded by the number of edges in \mathcal{A}' , which is $\mathcal{O}(n^2)$. \square

Since there are $\mathcal{O}(\frac{1}{\varepsilon^2})$ pairs of vectors in T_ε , we immediately obtain:

Theorem 4 Given a set of n lines \mathcal{L} , the arrangement of ε -placements of a unit square has complexity $\mathcal{O}(\frac{n^2}{\varepsilon^2})$.

3 Extensions

Here we describe how to extend the general approach when placing a square on lines to different, more realistic settings. We describe what happens when we replace the line arrangement with an arrangement of line segments, denoted $\mathcal{A}(\mathcal{T})$. Additionally, we describe how to adapt the approach when placing a circle rather than a square.

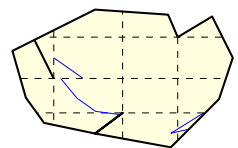


Figure 5: A non-convex cell c , its subdivision, and the (blue) curves $S(c, \tau)$.

3.1 Square on line segments

The definition of an ε -placement remains the same when we place a square amidst line segments, and again we study the complexity of the ε -placement space. In a

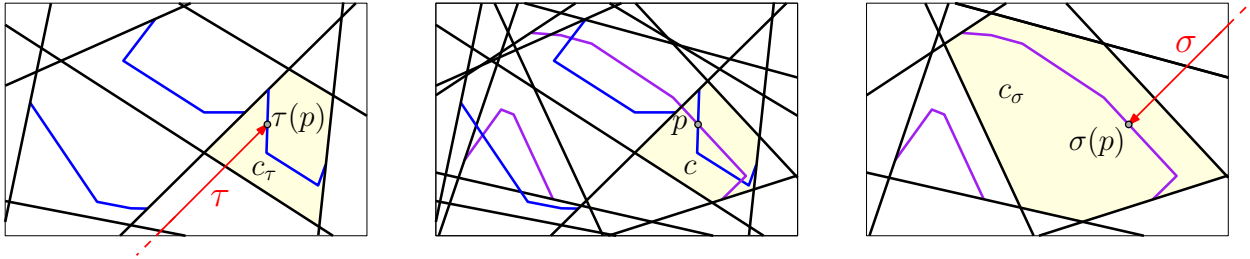


Figure 4: Example arrangement with ε -placements for two vectors τ and σ . Left: \mathcal{L} and $\tau(S(\tau))$. Right: \mathcal{L} and $\sigma(S(\sigma))$. Center: Both combined under appropriate translations.

nonconvex cell c of the arrangement, the curve $S(c, \tau)$ is no longer a piecewise linear convex curve, but it can have several disconnected pieces; see Figure 5.

Theorem 5 *Given a set of line segments \mathcal{T} , the arrangement of ε -placements of a unit square has complexity $\mathcal{O}(\frac{n^2}{\varepsilon^2})$.*

Proof. For analysis purposes, we imagine that any non-convex cell c of $\mathcal{A}(\mathcal{T})$ is partitioned into convex subcells as follows. For each endpoint of a line segment, shoot a ray in each orthogonal direction inside the cell until it hits another line segment. Use these rays to subdivide the cell into convex subcells, see Figure 5. If a cell c has k endpoints in its boundary, it is partitioned into $\mathcal{O}(k^2)$ subcells. Within each subcell of c , the curve $S(c, \tau)$ has the same properties as in a convex cell, and hence we can apply the same arguments as before. The total number of endpoints is $\mathcal{O}(n)$, and hence the total number of subcells analyzed in the arrangement $\mathcal{A}(\mathcal{T})$ is $\mathcal{O}(n^2)$. The bound follows. \square

3.2 Circle on lines

We now place a unit circle, \bigcirc_p , on \mathcal{L} , rather than a square. We again define a set of translation vectors T_ε to points ε -spaced on the boundary of \bigcirc_p , this time assuming $2\pi/\varepsilon$ is an integer. Consider cell c in the arrangement \mathcal{A} . The segments in $S(c, \tau)$ are no longer straight, but are generally elliptic.

Lemma 6 *The ε -placements of a circle such that the corresponding ε -segments lie in c form a collection of segments and elliptic arcs.*

Proof. Consider two lines ℓ_1 and $\ell_2 \in \mathcal{L}$. Consider a coordinate system with the origin in the intersection point of ℓ_1 and ℓ_2 and oriented such that ℓ_1 has equation $y = ax$, and ℓ_2 has equation $y = -ax$. Consider an ε -placement of a unit circle such that the ε -segment is in the I- and IV-quadrants below line ℓ_1 and above ℓ_2 as in Figure 6.

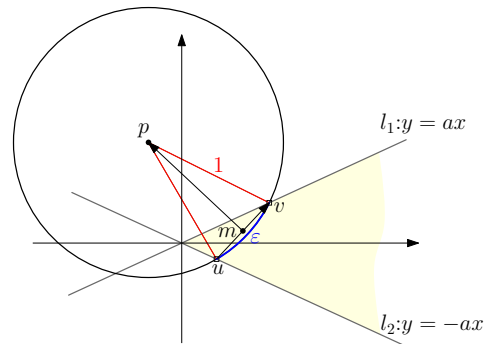


Figure 6: Two lines $\ell_1, \ell_2 \in \mathcal{L}$ and an ε -placement of p such that the corresponding ε -segment is in the highlighted region.

Let u be the intersection point of the circle and line ℓ_2 , v be the intersection of the circle and ℓ_1 , and m be a middle point between u and v . From the following equations:

$$\begin{aligned} |uv|^2 &= 2 - 2 \cos \varepsilon, \\ |up| &= 1, \\ |vp| &= 1, \\ \vec{u}\vec{p} \times \vec{m}\vec{p} &= |up| \cdot |mp|, \end{aligned}$$

we can derive that the segment of the ε -placement curve that corresponds to all such ε -segments that have one end point on line ℓ_1 and another end on ℓ_2 is an arc of an ellipse given by the following equation (refer to Figure 7):

$$\frac{a^2 x^2}{\left(\sin\left(\frac{\varepsilon}{2}\right) - a \cos\left(\frac{\varepsilon}{2}\right)\right)^2} + \frac{y^2}{\left(a \sin\left(\frac{\varepsilon}{2}\right) + \cos\left(\frac{\varepsilon}{2}\right)\right)^2} = 1.$$

\square

From this analysis we see that a sequence of adjacent arcs is not necessarily convex: when $a > \tan \frac{\varepsilon}{2}$ the point p is tracing the left arc of an ellipse (the convex part), when $a < \tan \frac{\varepsilon}{2}$ point p is tracing the right arc of an ellipse (the concave part), and when $a = \tan \frac{\varepsilon}{2}$ the ellipse

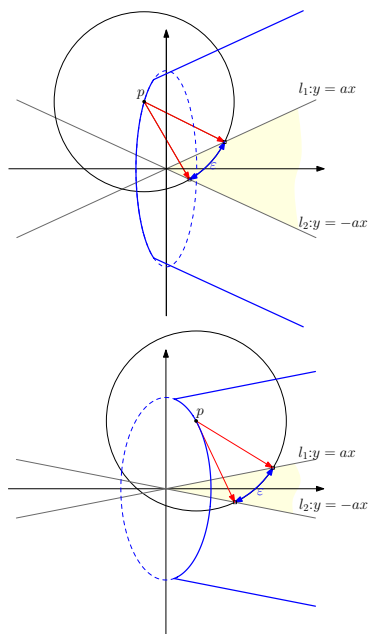


Figure 7: Two lines $\ell_1, \ell_2 \in \mathcal{L}$ and the curve (blue) that p traces over all ε -placements such that the corresponding ε -segments are within the highlighted region.

degenerates to a straight segment. Nonetheless, we can show that this cannot happen arbitrarily often.

Lemma 7 For $\varepsilon < 1$, $S(c, \tau)$ consists of a constant number of piece-wise elliptic convex curves.

Proof. Consider the sequence of angles a_1, a_2, \dots, a_k between consecutive edges of c . Because c is convex, we know that $\sum_{i=1}^k (\pi - a_i) = 2\pi$. For sufficiently small ε ($\varepsilon < 1$ suffices), this implies that no more than two angles a_i can be smaller than $\pi - \tan \frac{\varepsilon}{2}$.

By the previous lemma, these at most two angles correspond to concave elliptic arcs, which we report as separate curves. The remainder of the arcs and segments formed by boundary of c is subdivided by these gaps into at most two piece-wise elliptic convex curves.

As in the case for squares (refer to Lemma 1), at most two disconnected curves, each of which can be decomposed into at most four convex subcurves, may exist for any given τ . To see this, consider any line with direction τ that intersects c in a segment s . As we slide $\tau(p)$ along s , the length of the boundary piece of \bigcirc_p containing the point $\tau(p)$ in c changes as a concave function. Hence, the piece is an ε -segment at most twice. (Note that, in contrast to the square case, it is essential that s has orientation τ .) \square

To bound the complexity of the placement space, it is sufficient to bound the number of intersection points between $S(\tau)$ and $S(\sigma)$.

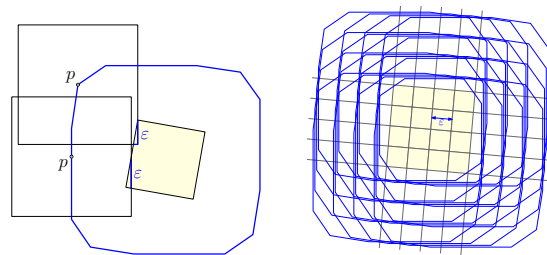


Figure 8: Lower bound construction for squares. (left) Point p traces an “offset” around square cell. (right) A $\frac{n}{2} \times \frac{n}{2}$ grid formed by lines from \mathcal{L} . Each cell has size $\mathcal{O}(\varepsilon)$.

Lemma 8 For distinct $\tau, \sigma \in T_\varepsilon$, the intersection of $S(\tau)$ and $S(\sigma)$ contains $\mathcal{O}(n^2)$ points.

Proof. Let \mathcal{A}' be the overlay of $\tau^{-1}(\mathcal{A})$ and $\sigma^{-1}(\mathcal{A})$: the arrangement of two copies of \mathcal{L} translated by the inverses of τ and σ . Let c be a cell in \mathcal{A}' , let c_τ and c_σ denote the cells in \mathcal{A} which respectively contain $\tau(p)$ and $\sigma(p)$. Observe that $c = \tau^{-1}(c_\tau) \cap \sigma^{-1}(c_\sigma)$.

Now, by Lemma 7, c_τ and c_σ both contain a constant number of (pieces of) convex curves. Each curve piece itself may consist of many elliptic arcs. We observe that a convex curve, consisting of k elliptic arcs, and a second convex curve, consisting of h elliptic arcs, may cause at most $\mathcal{O}(k + h)$ intersections. We thus charge the intersections to the pieces of $S(\tau)$ or $S(\sigma)$, and note that each piece is charged at most constantly often. \square

As in the case of squares, we have $\mathcal{O}(1/\varepsilon^2)$ distinct translation vectors, so we can bound the total complexity by $\mathcal{O}(n^2/\varepsilon^2)$.

Theorem 9 Given a set of n lines \mathcal{L} , the arrangement of ε -placements of a unit circle has complexity $\mathcal{O}(\frac{n^2}{\varepsilon^2})$.

4 Lower bounds

By a worst case construction we show a tight bound on the complexity of the placement space of a square (the construction for placing a circle is analogous). Consider a (slightly tilted) square cell of size $\mathcal{O}(\varepsilon)$. The curve traced by p of all ε -placements of a unit side square such that an ε -segment is inside the cell is shown in Figure 8. It forms an “offset” curve around the cell of width ≈ 2 . Place $\frac{n}{2}$ almost horizontal lines and $\frac{n}{2}$ almost vertical lines to form a grid with cells of size $\mathcal{O}(\varepsilon)$ (consider all lines slightly tilted). Figure 8 shows this construction.

A trivial upper bound² on the complexity of the placement space is $\mathcal{O}(n^4)$, which by our construction is worst

²If ε is arbitrarily small, the arrangement of the placement space is a collection of n^2 unit squares which can intersect pairwise.

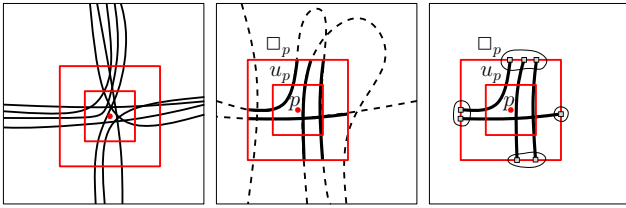


Figure 9: Left: Junction-like point with its two concentric squares. Middle: Solid subtrajectories are salient for the junction. Right: ε -clustering of the salient subtrajectory endpoints, revealing four arms.

case tight if $\varepsilon = \mathcal{O}(\frac{1}{n})$. If ε is bounded from below, the parametrized complexity of the arrangement is also worst-case tight.

Corollary 10 *Given a set of n lines \mathcal{L} and a parameter $\varepsilon = \Omega(\frac{1}{n})$, the arrangement of ε -placements has a worst case complexity $\Omega(\frac{n^2}{\varepsilon^2})$.*

5 Applications to junction detection

While junctions are normally features of (road) networks, our objective is to extract junctions purely based on trajectory data. This allows us to identify regions that serve as junctions in open spaces like city squares, or to identify places where animals pass by and choose one or the other direction.

We describe basic properties of a junction, which motivate corresponding definitions. Our approach is to treat any point in the plane as a potential junction; we define when a point is *junction-like* depending on the trajectories in its neighborhood. We show that the arrangement from Section 2 can be used to partition the plane into regions of points that are similarly junction-like, that is to say they have the same basic properties. In the full version of the paper [14] we present—as a proof of concept—the output of a prototype implementation run on idealized data.

Properties of a junction. A junction is a region where trajectories enter and leave in a limited number of directions or routes, called *arms* of the junction. While the moving entities initiate a direction to leave the junction in the core area, the arms are only “visible” somewhat further away from the core; see Figure 9. This motivates the use of two concentric squares to decide whether a point is junction-like. The way in which the trajectories enter and leave the two squares determines whether the point is junction-like and how significant that junction is. Since we can scale the plane with all trajectories, we can assume that the larger square is unit-size. We let the smaller square have side length $\frac{1}{2}$.

For a point p in the plane, let u_p and \square_p denote the boundaries of squares with side length $\frac{1}{2}$ and 1, respectively, both centered at p .

Definition 3 *A (sub)trajectory T is salient for a point p if it lies completely inside \square_p , it intersects u_p , and its endpoints lie on \square_p .*

From a set \mathcal{T} of trajectories we consider all subtrajectories that are salient; see Figure 9. Such subtrajectories should be maximal: their endpoints must be actual crossings with the boundary of \square_p and not just contacts. A single trajectory in \mathcal{T} can have multiple salient subtrajectories.

Definition 4 *Given a set of points Q on the boundary of a square \square_p and a constant $\varepsilon > 0$, an ε -clustering is a partitioning of Q such that for any two points $q, q' \in Q$ belonging to the same cluster, there exists a sequence of points $q = q_1, \dots, q_j = q'$, all in Q , such that q_i and q_{i+1} for $1 \leq i < j$ have distance at most ε along \square_p .*

Definition 5 *Let p be a point in the plane, let \mathcal{T} be a set of trajectories, let $\varepsilon > 0$, and let $Q_p(\mathcal{T})$ be the set of endpoints of all salient subtrajectories from \mathcal{T} . A point p is junction-like if an ε -clustering of $Q_p(\mathcal{T})$ has at least three clusters.*

When we move the point p over the plane, these clusters can grow, shrink, merge and split. A cluster may for instance split when two consecutive intersection points from $Q_p(\mathcal{T})$ become more separated than ε . A cluster may shrink because a subtrajectory is no longer salient, which then may also cause a split of a cluster.

It should be clear that we can compute a subdivision of the plane into maximal cells where the ε -clustering is the same. It should also be clear that the theory of Section 2 discusses a simplified version of this problem where salience is not considered.

Implementation and results. There are many ways to obtain junctions from the junction-like points and their ε -clustering. There are also many ways to attach a significance to a junction, based on the number of clusters and their sizes. Moreover, we may want to distinguish between *real junctions* and *crossings*, where a crossing is a junction-like region with four arms where all trajectories go straight, and a real junction has several different splits and merges of trajectories over the clusters. For both types we can define their significance in various ways. This is beyond the scope of this paper; see [13, 14] for further discussions.

6 Conclusions and further research

We analyzed the complexity of the placement space of a unit square or circle in an arrangement of lines or line

segments, a problem that lies at the core of junction detection in trajectory analysis. Our results include upper bounds that improve on the naive $O(n^4)$ bound by showing that two of the linear factors in fact only need to depend on $1/\varepsilon$. Increasing the number of trajectories is not a reason to increase the granularity of the clustering, so in practice we expect $1/\varepsilon$ to be much smaller than n , if not constant. The resulting $\Theta(n^2/\varepsilon^2)$ bound is tight in the worst case. The combinatorial problem is interesting from the theoretical perspective because it combines arrangements with distances in the arrangement.

A prototype implementation applies the result to junction detection. While the implementation demonstrates the value of the approach and indicates that the time complexity is not prohibitive, several simplifications of the problem have been made and no extensive experiments have been performed. In a follow-up study, it would be interesting to augment the implementation with circles or different shapes, and to run the algorithm on real-world trajectory data from various sources.

From a theoretical perspective, it would be interesting to explore further extensions of the approach (i.e. curved trajectories, trajectories embedded in higher-dimensional spaces), or apply it to other distance based arrangements.

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