Classifying convex bodies by their contact and intersection graphs

Aamand, Anders; Abrahamsen, Mikkel; Knudsen, Jakob Bæk Tejs; Rasmussen, Peter Michael Reichstein

Published in:
37th International Symposium on Computational Geometry, SoCG 2021

DOI:
10.4230/LIPIcs.SoCG.2021.3

Publication date:
2021

Document version
Publisher's PDF, also known as Version of record

Document license:
CC BY

Citation for published version (APA):
https://doi.org/10.4230/LIPIcs.SoCG.2021.3
Classifying Convex Bodies by Their Contact and Intersection Graphs

Anders Aamand
BARC, University of Copenhagen, Denmark
Mikkel Abrahamsen
BARC, University of Copenhagen, Denmark
Jakob Bæk Tejs Knudsen
BARC, University of Copenhagen, Denmark
Peter Michael Reichstein Rasmussen
BARC, University of Copenhagen, Denmark

Abstract
Let $A$ be a convex body in the plane and $A_1, \ldots, A_n$ be translates of $A$. Such translates give rise to an intersection graph $G = (V, E)$, with vertices $V = \{1, \ldots, n\}$ and edges $E = \{uv | A_u \cap A_v \neq \emptyset\}$. The subgraph $G' = (V, E')$ satisfying that $E' \subset E$ is the set of edges $uv$ for which the interiors of $A_u$ and $A_v$ are disjoint is a unit distance graph of $A$. If furthermore $G' = G$, i.e., if the interiors of $A_u$ and $A_v$ are disjoint whenever $u \neq v$, then $G$ is a contact graph of $A$.

In this paper, we study which pairs of convex bodies have the same contact, unit distance, or intersection graphs. We say that two convex bodies $A$ and $B$ are equivalent if there exists a linear transformation $B'$ of $B$ such that for any slope, the longest line segments with that slope contained in $A$ and $B'$, respectively, are equally long. For a broad class of convex bodies, including all strictly convex bodies and linear transformations of regular polygons, we show that the contact graphs of $A$ and $B$ are the same if and only if $A$ and $B$ are equivalent. We prove the same statement for unit distance and intersection graphs.

2012 ACM Subject Classification Theory of computation → Computational geometry; Mathematics of computing → Graph theory; Mathematics of computing → Discrete mathematics

Keywords and phrases convex body, contact graph, intersection graph

Digital Object Identifier 10.4230/LIPIcs.SoCG.2021.3


Funding The authors are part of BARC, Basic Algorithms Research Copenhagen, supported by the VILLUM Foundation grant 16582.

Acknowledgements We thank Tillmann Miltzow for asking when the translates of two different convex bodies induce the same intersection graphs which inspired us to work on these problems.

1 Introduction
Consider a convex body $A$, i.e., a convex, compact region of the plane with non-empty interior, and let $A = \{A_1, \ldots, A_n\}$ be a set of $n$ translates of $A$. Then $A$ gives rise to an intersection graph $G = (V, E)$, where $V = \{1, \ldots, n\}$ and $E = \{uv | A_u \cap A_v \neq \emptyset\}$, and a unit distance graph $G' = (V, E')$, where $uv \in E'$ if and only if $uv \in E$ and $A_u$ and $A_v$ have disjoint interiors. In the special case that $G = G'$ (i.e., the convex bodies of $A$ have pairwise disjoint interiors), we say that $G$ is a contact graph (also known as a touch graph or tangency graph). Thus, $A$ defines three classes of graphs, namely the intersection graphs $I(A)$, the unit distance graphs $U(A)$, and the contact graphs $C(A)$ of translates of $A$. 

© Anders Aamand, Mikkel Abrahamsen, Jakob Bæk Tejs Knudsen, and Peter Michael Reichstein Rasmussen; licensed under Creative Commons License CC-BY 4.0
The study of intersection graphs has been an active research area in discrete and computational geometry for the past three decades. For instance, numerous papers consider the problem of solving classical graph problems efficiently on various classes of geometric intersection graphs; see Section 1.1 for some references. Meanwhile, the study of contact graphs of translates of a convex body has much older roots. It is closely related to the packings of such a body, which has a very long and rich history in mathematics going back (at least) to the seventeenth century, where research on the packings of circles of varying and constant radii was conducted and Kepler famously conjectured upon a 3-dimensional counterpart of such problems, the packing of spheres.

In this paper we investigate the question of when two convex bodies $A$ and $B$ give rise to the same classes of graphs. We restrict ourselves to convex bodies $A$ that have the URTC property (unique regular triangle constructibility). This is the property that given two interior disjoint translates $A_1, A_2$ of $A$ that touch, there are exactly two ways to place a third translate $A_3$ such that $A_3$ is interior disjoint from $A_1$ and $A_2$, but touches both. Convex bodies with the URTC property include all linear transformations of regular polygons except squares and all strictly convex bodies [15]. Thus, almost all convex bodies in a measure theoretic sense have the property [15, 18, 30]. A convex body without the property must have a sufficiently long line segment on the boundary (to be made precise in Section 1.3); see Figure 1 for an example.

The main result of the paper is summarized in the following theorem.

**Theorem 1.** Let $A$ and $B$ be convex bodies with the URTC property. Then each of the identities $I(A) = I(B)$, $U(A) = U(B)$, and $C(A) = C(B)$ holds if and only if the following condition is satisfied: there is a linear transformation $B'$ of $B$ such that for any slope, the longest segments contained in $A$ and $B'$, respectively, with that slope are equally long.

If the condition from the theorem is satisfied, we say that $A$ and $B$ are equivalent. The length of the longest segment with a given slope contained in a convex body $A$ is often called the width of $A$ in the corresponding direction. A circle has constant width but there are other convex bodies of constant width, the simplest example being the Reuleaux triangle; see Figure 2. As an example it follows from the theorem that circles and Reuleaux triangles have the same contact, unit distance, and intersection graphs, which in turn are the same as those for ellipses (ellipses are linear transforms of circles). It also follows that these classes are different from those of regular hexagons.
Figure 3 The strength of radiation in every direction and at various frequencies for two different transmitters described in [25]. In engineering circles, this known as the radiation pattern.

Figure 4 When the reachable region of a device is symmetric and the devices are oriented in the same way, a communication network is the intersection graph of the reachable region scaled by $1/2$. Left: A network of five identical devices with the reachable regions shown. Right: The intersection graph of the reachable regions scaled by $1/2$.

1.1 Practical Implications

From a practical point of view, the research on intersection graphs is often motivated by the applicability of these graphs when modeling wireless communication networks and facility location problems. If a device is located at some point in the plane and is able to transmit to and receive from all other devices within some distance, then the devices can be represented as unit disks in such a way that two devices can communicate if and only if their disks overlap. Many highly-cited papers gave this motivation for studying unit disk intersection graphs [9, 14, 16, 21, 29] and it remains a motivation for new research [7, 12, 13, 24].

However, it is in general not the case that a transmitter emits an equally strong signal in all directions. For a real-world example of how the signal strength may vary in different directions; see Figure 3. If the networks that can be made with devices of a given type are not the unit disk intersection graphs, the algorithms for unit disk graphs cannot be expected to work when applied to the actual networks. It is therefore necessary to study how the possible networks that can be made with devices of different types depend on the radiation pattern of the devices. See Figure 4 for a demonstration of the connection between communication networks of a device with a non-circular radiation pattern and intersection graphs of the corresponding convex body.
1.2 Other Related Work

An important notion in the area of contact graphs is that of the **Hadwiger number** of a body \( K \), which is the maximum possible number of pairwise interior-disjoint translates \( K_i \) of \( K \) that each touch but do not overlap \( K \). The Hadwiger number of \( K \) is thus the maximum degree of a contact graph of translates of \( K \). In the plane, the Hadwiger number is 8 for parallelograms and 6 for all other convex bodies. We refer the reader to the books and surveys by László and Gábor Fejes Tóth [28, 10] and Böröczky [3].

Another noteworthy result on contact graphs is the Circle Packing Theorem (also known as the Koebe–Andreev–Thurston Theorem): A graph is simple and planar if and only if it is the contact graph of some set of circular disks in the plane (the radii of which need not be equal). The result was proven by Koebe in 1935 [19] (see [11] for a streamlined, elementary proof). Schramm [26] generalized the circle packing theorem by showing that if a planar convex body with smooth boundary is assigned to each vertex in a planar graph, then the graph can be realized as a contact graph where each vertex is represented by a homothet (i.e., a scaled translation) of its assigned body.

Several papers have compared classes of intersection graphs of various geometric objects, see for instance [4, 6, 8, 17, 20]. Most of the results are inclusions between classes of intersection graphs of one-dimensional objects such as line segments and curves.

A survey by Swanepoel [27] summarizes results on minimum distance graphs and unit distance graphs in normed spaces, including bounds on the minimum/maximum degree, maximum number of edges, chromatic number, and independence number.

In the area of computational geometry, Müller, van Leeuwen, and van Leeuwen [23] gave sharp upper and lower bounds on the size of an integer grid used to represent an intersection graph of translates of a convex polygon with corners at rational coordinates. Their results imply that for any convex polygon \( R \) with rational corners, the problem of recognizing intersection graphs of translates of \( R \) is in NP. On the contrary, it is open whether recognition of unit disk intersection graphs in the Euclidean plane is in NP. Indeed, the problem is \( \exists \mathbb{R} \)-complete (and thus in PSPACE), and using integers to represent the center coordinates and radii of the disks in some graphs requires exponentially many bits [5, 22].

Bonnet, Grelier, and Miltzow [2] showed how well-known algorithms for the clique problem in unit disk intersection graphs and disk intersection graphs can be adjusted to work for intersection graphs of translates or homothets of an arbitrary centrally symmetric convex body.

1.3 Preliminaries

We begin by defining some basic geometric concepts and terminology.

For a subset \( A \subset \mathbb{R}^2 \) of the plane we denote by \( A^o \) the interior of \( A \), that is,

\[ A^o = \{ x \in A \mid \exists \text{ open } U \subset \mathbb{R}^2 \text{ such that } \{ x \} \subset U \subset A \}. \]

We say that \( A \) is a **convex body** if \( A \) is compact, convex, and has non-empty interior. We say that \( A \) is **symmetric** if whenever \( x \in A \), then \(-x \in A \). It is well-known that if \( A \) is a symmetric convex body, then the map \( \| \cdot \|_A : \mathbb{R}^2 \to \mathbb{R}_{\geq 0} \) defined by

\[ \| x \|_A = \inf \{ \lambda \geq 0 \mid x \in \lambda A \}, \]

is a norm. Moreover \( A = \{ x \in \mathbb{R}^2 \mid \| x \|_A \leq 1 \} \) and \( A^o = \{ x \in \mathbb{R}^2 \mid \| x \|_A < 1 \} \).

It follows from these properties that for translates \( A_1 = A + v_1 \) and \( A_2 = A + v_2 \) it holds that \( A_1 \cap A_2 \neq \emptyset \) if and only if \( \| v_1 - v_2 \|_A \leq 2 \) and \( A_1^o \cap A_2^o \neq \emptyset \) if and only if \( \| v_1 - v_2 \|_A < 2 \). This means that when studying contact, unit distance, and intersection
graphs of a symmetric convex body \(A\), we can shift our viewpoint from translates of \(A\) to point sets in \(\mathbb{R}^2\) and their \(\|\cdot\|_A\)-distances: If \(A \subseteq \mathbb{R}^2\) is a set of points we define \(I_A(A)\) and \(U_A(A)\) to be the graphs with vertex set \(A\) and edge sets \(\{(x, y) \in A^2 \mid x \neq y \text{ and } \|x - y\|_A \leq 2\}\) and \(\{(x, y) \in A^2 \mid \|x - y\|_A = 2\}\), respectively. Moreover, if for all distinct points \(x, y \in A\) it holds that \(\|x - y\|_A \geq 2\), we say that \(A\) is compatible with \(A\) and define \(C_A(A)\) to be the graph with vertex set \(A\) and edge set \(\{(x, y) \in A^2 \mid \|x - y\|_A = 2\}\). Then \(I_A(A), U_A(A),\) and \(C_A(A)\), respectively, are isomorphic to the intersection, unit distance, and contact graph of \(A\) realized by the translates \((A + a)_{a \in A}\). When studying contact, unit distance, and intersection graphs of a symmetric, convex body \(A\) we will view them as being induced by point sets rather than by translates of \(A\).

We say that a (not necessarily symmetric) convex body \(A\) in the plane has the URTC property if the following holds: For any two interior disjoint translates of \(A\), \(A_1\) and \(A_2\), satisfying \(A_1 \cap A_2 \neq \emptyset\), there exists precisely two vectors \(v \in \mathbb{R}^2\) such that for \(i \in \{1, 2\}\), \((A + v)^i \cap A^i_2 = \emptyset\) but \((A + v) \cap A_i \neq \emptyset\). If \(A\) is symmetric, this amounts to saying that for any two points \(v_1, v_2 \in \mathbb{R}^2\) with \(\|v_1 - v_2\|_A = 2\), the set \(\{v \in \mathbb{R}^2 \mid \|v - v_1\|_A = \|v - v_2\|_A = 2\}\) has size two. Gehér [15] proved that a symmetric convex body \(A\) has the URTC property if and only if the boundary \(\partial A\) does not contain a line segment of length more than 1 in the \(\|\cdot\|_A\)-norm. See Figure 1 for an example of a convex body not having the URTC property.

A drawing of a graph \(G \subseteq I(A)\) as an intersection graph of a symmetric convex body \(A\) is a point set \(A \subseteq \mathbb{R}^2\) and a set of straight line segments \(L\) such that \(I_A(A)\) is isomorphic to \(G\) and \(L\) is exactly the line segments between the points \(u, v \in A\) which are connected by an edge in \(G\). We define a drawing of a graph \(G\) as a contact and unit distance graph similarly.

For a norm \(\|\cdot\|\) on \(\mathbb{R}^2\) and a line segment \(\ell\) with endpoints \(a\) and \(b\) we will often write \(\|\ell\| = \|ab\|\) instead of \(\|a - b\|\). Also, if \(A\) is a symmetric convex body and \(U, V \subseteq \mathbb{R}^2\), we define \(d_A(U, V) := \inf\{\|uv\|_A \mid (u, v) \in U \times V\}\).

### 1.4 Structure and Techniques of the Paper

Establishing the sufficiency of the condition of Theorem 1, i.e., showing that if \(A\) and \(B\) are equivalent then \(I(A) = I(B), U(A) = U(B),\) and \(C(A) = C(B)\), is relatively straightforward and has been deferred to the full version of the paper. It is also relatively easy to reduce Theorem 1 to the case where the convex bodies are symmetric so this too is deferred to the full version. When both \(A\) and \(B\) are symmetric, they are equivalent according to the condition of Theorem 1 if and only if they are linear transformations of each other.

Thus, left with the task of proving the necessity of the condition of Theorem 1 in the symmetric case, we proceed in two steps. First, in Section 2, we prove the following result, which for contact and unit distance graphs is a generalization of this direction of Theorem 1.

**Theorem 2.** Let \(A\) and \(B\) be symmetric convex bodies with the URTC property such that \(A\) is not a linear transformation of \(B\). There exists a graph \(G \subseteq C(A)\) such that for all \(H \subseteq C(B)\) and all subgraphs \(H' \subseteq H\), \(G\) is not isomorphic to \(H'\). In particular \(C(A) \setminus C(B) \neq \emptyset\).

As we will also discuss in Section 2 the same result holds if \(C(X)\) is replaced by \(U(X)\) for \(X \in \{A, B\}\) everywhere in the theorem above and the proof is identical.

The core idea in proving Theorem 2 is to consider a graph \(G\) satisfying that any drawing of \(G\) as a contact graph of \(A\) has certain structural properties. Concretely, we ensure that any drawing of \(G\) as a contact graph of \(A\) consists of many large hollow hexagons. In the interior of each hexagon, we force there to be a “bridge” of translates of \(A\) connecting the...
Classifying Convex Bodies by Their Contact and Intersection Graphs

sides of the hexagon. We show that if \( B \) is not a linear transformation of \( A \), then the contact graph cannot be realized by translates of \( B \) if we make sufficiently many and sufficiently large hexagons with bridges of different slopes. See Figures 6 and 7 for illustrations.

To include intersection graphs, we proceed with the second step. In Section 3, we prove the following result which combined with Theorem 2 immediately yields the necessity of the condition of Theorem 1 for intersection graphs.

**Theorem 3.** Let \( A \) and \( B \) be symmetric convex bodies. If there exists a graph \( G \in C(A) \) such that for all \( H \in C(B) \) and all subgraphs \( H' \subset H \), \( G \) is not isomorphic to \( H' \), then \( I(A) \neq I(B) \).

This result holds for general symmetric convex bodies. An improvement of Theorem 2 to general symmetric convex bodies (not necessarily having the URTC property) would thus yield a version of Theorem 1 that also holds for general convex bodies.

In order to prove Theorem 3, we proceed as follows. For every positive integer \( k \) we construct a gadget \( Q_k \in I(A) \) which contains as a subgraph a distinguished cycle \( \alpha_k \subset Q_k \).

We prove that in any drawing of \( Q_k \) as an intersection graph of translates of \( A \), \( \alpha_k \) is contained in a translation of the annulus \( kA \setminus (k-1)A \) (here, \( kA = \{ka \mid a \in A \} \) is the scaling of \( A \) by \( k \)). This allows us to view \( \alpha_k \) as an upscaled copy of the boundary of \( A \) with a precision error decreasing in \( k \). Similarly, in any drawing of the same gadget \( Q_k \) as an intersection graph of another body, \( B \), the cycle \( \alpha_k \) appears as an upscaled copy of \( B \). The idea is then to simulate a contact graph \( G \in C(A) \) using distinct copies of \( Q_k \), where each copy plays the role of a single vertex in \( G \). If \( A \) is not a linear transformation of \( B \), we can choose \( G \) with the properties promised in Theorem 2. We are then able to prove that if we choose \( k \) sufficiently large (i.e., obtaining sufficiently high resemblance between \( \alpha_k \) and an upscaled copy of \( A \) resp. \( B \)), then we can realize the simulation of \( G \) as an intersection graph using translates of \( A \), but not using translates of \( B \). This then implies \( I(A) \neq I(B) \) as desired.

Beyond aiding us in the proof of our main theorem, we believe that this proof technique – the reduction from intersection to contact graphs – is of independent interest. It appears a novel approach with the potential to answer other questions on intersection graphs.

## 2 Contact and Unit Distance Graphs

In this section we prove Theorem 2. The proof for unit distance graphs is completely identical so we will merely provide a remark justifying this claim by the end of the section.

Throughout the section \( A \) and \( B \) will denote symmetric convex bodies. For \( \theta \in [0,2\pi) \) we define \( e_A(\theta) \) to be the vector of argument \( \theta \) and with \( \|e_A(\theta)\|_A = 1 \). We also define \( \rho_A(\theta) = 2\|e_A(\theta)\|_2 \). Then \( \rho_A(\theta) \) can be thought of as the “diameter” of \( A \) in direction \( \theta \). One of our most important tools is the following lemma.

**Lemma 4.** Let \( A, B \) be symmetric convex bodies in \( \mathbb{R}^2 \). If for every finite set \( \Theta \subset [0,\pi) \) and for every \( \varepsilon > 0 \), there exists a linear map \( T : \mathbb{R}^2 \to \mathbb{R}^2 \) satisfying that \( |\rho_T(B)(\theta) - \rho_A(\theta)| < \varepsilon \) for all \( \theta \in \Theta \), then there exists a linear map \( T : \mathbb{R}^2 \to \mathbb{R}^2 \) with \( T(B) = A \).

Due to space limitations we have left out the proof, but it can be found in the full version.

We proceed to describe certain lattices which give rise to contact graphs that can only be realized in an essentially unique way. We start with the following definition.

**Definition 5.** Let \( A \subset \mathbb{R}^2 \) be a symmetric convex body, and \( \|\cdot\|_A \) the associated norm. Let \( e_1, e_2 \in \mathbb{R}^2 \) be such that \( \|e_1\|_A = \|e_2\|_A = \|e_1 - e_2\|_A = 2 \). We define the lattice \( \mathcal{L}_A(e_1,e_2) = \{a_1e_1 + a_2e_2 \mid (a_1,a_2) \in \mathbb{Z}^2 \} \).
The left hand side of figure Figure 6 illustrates the lattice structure. Let us assume that $A$ has the URTC property and describe a few properties of the lattice $\mathcal{L}_A(e_1, e_2)$. After choosing $e_1$ with $\|e_1\|_A = 2$, there are precisely two vectors $v$ with $\|v\|_A = \|v - e_1\|_A = 2$, using the URTC property. If one is $v_2$ the second is $e_1 - v_2$ so regardless how we choose $e_2$ we obtain the same lattice. Using the triangle inequality and the URTC property of $A$ it is easily verified that for distinct $x, y \in \mathcal{L}_A(e_1, e_2)$, $\|x - y\|_A \geq 2$ with equality holding exactly if $x - y \in \mathcal{S}_A := \{e_1, e_2, e_2 - e_1, -e_1, -e_2, e_1 - e_2\}$. This implies that the contact graph $G_0 := C_A(\mathcal{L}_A(e_1, e_2))$ is in fact (isomorphic to) an infinite triangular grid.

Another useful fact is the following:

**Lemma 6.** With $\mathcal{S}_A$ as above it holds that $\frac{1}{2} \text{conv}(\mathcal{S}_A) \subset A \subset \text{conv}(\mathcal{S}_A)$. Here $\text{conv}(\mathcal{S}_A)$ is the convex hull of $\mathcal{S}_A$. If in particular $B$ is another symmetric convex body for which $\|e_1\|_B = \|e_2\|_B = \|e_1 - e_2\|_B = 2$, then for all $x \in \mathbb{R}^2$ it holds that $\frac{1}{2} \|x\|_A \leq \|x\|_B \leq 2 \|x\|_A$.

**Proof.** See Figure 5. As $\frac{1}{2} \mathcal{S}_A \subset A$ and $A$ is convex the first inclusion is clear. For the second inclusion we note that all points $y$ on the hexagon connecting the points $e_1, e_2, -e_2, e_1 - e_2, -e_1, e_1 - e_2$ of $\mathcal{S}_A$ in this order have $\|y\|_A \geq 1$ by the triangle inequality and so $A \subset \text{conv}(\mathcal{S}_A)$.

For the last statement of the lemma note that if $x \in \mathbb{R}^2$ then

$$\|x\|_B \geq \inf_{\lambda \geq 0} \{x \in \lambda \text{conv}(\mathcal{S}_B)\} = \inf_{\lambda \geq 0} \{x \in \lambda \text{conv}(\mathcal{S}_A)\} \geq \inf_{\lambda \geq 0} \{x \in 2\lambda A\} = \frac{1}{2} \|x\|_A,$$

and similarly $\|x\|_A \geq \frac{1}{2} \|x\|_B$.

**Definition 7.** We say that a graph $G = (V, E)$ is lattice unique if $|V| = n \geq 3$ and there exists an enumeration of its vertices $v_1, \ldots, v_n$ such that

- The vertex induced subgraph $G[v_1, v_2, v_3] \simeq K_3$ is a triangle.
- For $i > 3$ there exists distinct $j, k, l < i$ such that $G[v_j, v_k, v_l] \simeq K_3$ and both $(v_i, v_j)$ and $(v_i, v_k)$ are edges of $G$.

Suppose that $A$ is a symmetric convex body with the URTC property, that $A \subset \mathbb{R}^2$ is compatible with $A$, and that $G = C_A(A)$ is lattice unique. Enumerate the points of $A = \{v_1, \ldots, v_n\}$ according to the definition of lattice uniqueness. Without loss of generality assume that $v_1 = 0$. Then the URTC property of $A$ combined with the lattice uniqueness of $G$ gives that $v_4, \ldots, v_n$ are uniquely determined from $v_2$ and $v_3$ and all contained in $\mathcal{L}_A(v_2, v_3)$. If moreover $B$ is another convex body with the URTC property, $B = \{v_1', \ldots, v_n'\} \subset \mathbb{R}^2$ has $v_1' = 0$ and is compatible with $B$, and $C_B(B) \simeq C_A(A)$ via the graph isomorphism $\varphi : v_i' \mapsto v_i$, then the linear map $T : \mathbb{R}^2 \to \mathbb{R}^2$ defined by $T : a_1v_2' + a_2v_3' \mapsto a_1v_2 + a_2v_3$ satisfies that $T|_B = \varphi$.

We will use this observation in the proof of Theorem 2 which we now provide.
We then wish to "attach" $A$ with $B$ along with the corresponding lattice unique subgraph $G_0[H_6]$. We choose $e_1, e_2 \in \mathbb{R}^2$ be such that $\|e_1\|_A = \|e_2\|_A = \|e_1 - e_2\|_A = 2$ and define the lattice $L := L_A(e_1, e_2)$. We also define the infinite graph $G_0 := C_A(L)$ which by the remarks following Definition 5 is isomorphic to the infinite triangular grid. Without loss of generality we can assume that $e_1$ and $e_2$ satisfy $\|e_1\|_2 = \|e_2\|_2 = \|e_1 - e_2\|_2 = 2$, since there exists a non-singular linear transformation $T$ such that $\|T(e_1)\|_2 = \|T(e_2)\|_2 = \|T(e_1) - T(e_2)\|_2 = 2$, and $C(A) = C(T(A))$. Note that in this setting we can use Lemma 6 to compare $A$ to the disk of radius 1 and obtain $\frac{1}{2}\|x\|_2 \leq \|x\|_A \leq 2\|x\|_2$ for every $x \in \mathbb{R}^2$.

We will construct $G$ by specifying a finite point set $A \subset \mathbb{R}^2$ compatible with $A$ and define $G = C_A(A)$. The construction of $A$ can be divided into several sub-constructions. We start by describing a hexagon of points $H_k$ for $k \in \mathbb{N}$ which satisfies that $C_A(H_k)$ is lattice unique.

**Construction 8 ($H_k$).** For an illustration of the construction see the left-hand side of Figure 6. For $x, y \in L$ we write $d(x, y)$ for the distance between $x$ and $y$ in the graph $G_0$, and for $k \in \mathbb{N}$ we define $H_k = \{x \in L \mid d(x, 0) \in \{k, k + 1\}\}$.

Using that $G_0$ is the infinite triangular grid, it is easy to check that $G_0[H_k]$ is a lattice unique graph by specifying an enumeration of its vertices satisfying the condition in Definition 7. Moreover, using that $e_1$ and $e_2$ satisfy $\|e_1\|_2 = \|e_2\|_2 = \|e_1 - e_2\|_2 = 2$ it follows that the points $\{x \in L \mid d(x, 0) = k\} \subset H_k$ lie on a regular hexagon $H_k$ whose corners have Euclidean distance exactly $2k$ to the origin. In particular any point $p \in H_k$ has $\|p\|_2 \geq \sqrt{3}k$, and thus $\|p\|_A \geq \frac{\sqrt{3}}{2}k$ by Lemma 6.

For a given $\theta \in [0, \pi)$ and $\ell \in \mathbb{N}$ we will construct a set of points $B_0(\ell) \subset \mathbb{R}^2$ compatible with $A$ which constitute a "beam" of argument $\theta$:

**Construction 9 ($B_0(\ell)$).** See Figure 6 (right). Let $e_0 \in \mathbb{R}^2$ be the vector of argument $\theta$ with $\|e_0\|_A = 2$, and let $f_0 \in \mathbb{R}^2$ be such that $\|f_0\|_A = \|f_0 - e_0\|_A = 2$ (by the URTC property we have two choices for $f_0$). For a given $\ell \in \mathbb{N}$ we define $B_0(\ell) = \{ae_0 \mid a \in \{-\ell, \ldots, \ell\}\} \cup \{ae_0 + f_0 \mid a \in \{-\ell, \ldots, \ell - 1\}\}$

As $B_0(\ell) \subset L_A(e_0, f_0)$ it is compatible with $A$. Moreover it is easy to specify an enumeration of the vertices of $C(B_0(\ell))$ showing that it is lattice unique.

For a given $k$ we want to choose $\ell$ as large as possible such that $B_0(\ell)$ "fits inside" $G_0[H_k]$. We then wish to "attach" $B_0(\ell)$ to $G_0[H_k]$ with extra points $S$, the number of which does neither depend on $k$ nor on $\theta$. We wish to do it in such a way that $A_k^*(\theta) := B_0(\ell) \cup G_0[H_k] \cup S$ is compatible with $A$. The precise construction is as follows:
That we can scale the deviation to be multiplicative rather than additive is possible because in numerous ways to satisfy this. One is depicted in Figure 7. Another is obtained by is compatible with 0

\[ \theta \in [0, \pi] \]

be the combination of the components completes the construction. 

We define \( \theta \in [0, \pi] \) and \( \rho \in \{ \theta \} \) similarly define \( B \) and \( A \) to connect the other end. See Figure 6 (right). In the full version we show that \( |S_1(\theta)| \leq 13 \) for \( i \in \{1, 2\} \). Letting \( C_k(\theta) = H_k \cup B_{a_\theta}(\ell) \cup S_1(\theta) \cup S_2(\theta) \cup \{ z_1^\theta, z_2^\theta \} \) be the combination of the components completes the construction.

We are now ready to construct \( A \) which will consist of several translated copies \( C_k(\theta) \).

**Construction 11 (\( A \)).** By Lemma 4 we can find an \( \varepsilon \in (0, 1) \) and a finite set of directions \( \Theta \subset [0, \pi] \) such that for all linear maps \( T : \mathbb{R}^2 \to \mathbb{R}^2 \) there exists \( \theta \in \Theta \) such that 

\[ \left| \frac{\rho_A(\theta)}{\rho_T(\theta)} - 1 \right| \geq \varepsilon. \] (2)

That we can scale the deviation to be multiplicative rather than additive is possible because 

\[ 0 < \inf_{\theta \in [0, \pi]} \rho_A(\theta) \leq \sup_{\theta \in [0, \pi]} \rho_A(\theta) < \infty. \]

For each \( \theta \in \Theta \) we construct a copy of \( C_k(\theta) = H_k \cup B_{a_\theta}(\ell) \cup S_1(\theta) \cup S_2(\theta) \cup \{ z_1^\theta, z_2^\theta \} \) where \( k \) is yet to be fixed (\( \ell \) is of course determined by \( k \) and \( \theta \)). We then choose translations \( t_\theta \in \mathbb{R}^2 \) for each \( \theta \in \Theta \) such that the sets \((H_k + t_\theta)_{\theta \in \Theta}\) are pairwise disjoint, and \( \bigcup_{\theta \in \Theta} (H_k + t_\theta) \subset \mathbb{R}^2 \) is compatible with \( A \) and induces a lattice unique contact graph. We can choose \((t_\theta)_{\theta \in \Theta}\) in numerous ways to satisfy this. One is depicted in Figure 7. Another is obtained by
Classifying Convex Bodies by Their Contact and Intersection Graphs

We are now ready for the final step of the proof:

**Proving that no graph in** $C(B)$ **contains a subgraph isomorphic to** $G = C_A(A)$.

Suppose for contradiction that there exists a set of points $B \subset \mathbb{R}^2$ such that $G$ is isomorphic to a subgraph of $C_B(B)$. We may clearly assume that $|A| = |B|$ and we let $\varphi : A \to B$ be a bijection which is also a graph homomorphism when considered as a map $C_A(A) \to C_B(B)$. The points $\bigcup_{\theta \in \Theta}(H_k + t_\theta)$ induce a lattice unique contact graph of $A$. Thus, we may write $\bigcup_{\theta \in \Theta}(H_k + t_\theta) = \{p_1, \ldots, p_n\}$ such that $p_1, p_2$ and $p_3$ induce a triangle of $G$ and such that for $i > 3$ there exist distinct $j, k, l < i$ such that $p_j, p_k$ and $p_l$ induce a triangle and such that $(p_i, p_j)$ and $(p_i, p_k)$ are edges of $G$. By translating the point sets $A$ and $B$ we may assume that $\varphi(p_1) = p_1 = 0$. Then applying an appropriate linear transformation $T$, thus replacing $B$ by $T(B)$, we may assume that $\varphi(p_2) = p_2$ and $\varphi(p_3) = p_3$. Finally, the discussion succeeding Definition 7 implies that in fact $\varphi|_{\bigcup_{\theta \in \Theta}(H_k + t_\theta)}$ is the identity.

As noted in Construction 11, there exists $\theta \in \Theta$ such that $|\rho_A(\theta) - 1| \geq \varepsilon$. The outline of the remaining argument is as follows: The Euclidean distance between the “endpoints” of the beam $B_0(\ell)$ is $2(\rho_A(\theta))$, but the rigidity of $\bigcup_{\theta \in \Theta}(H_k + t_\theta)$ means that it is also $2(\rho_T(\theta)) + O(1)$. When $k$ (and hence $\ell$) is large, this will contradict the inequality above.

We refer the reader to the full version of the paper for the technical details.

**Remark 12.** We claimed that the proof of the part of Theorem 1 concerning unit distance graphs is identical to the proof above. In fact, if we replace $C(X)$ by $U(X)$ for $X \in \{A, B\}$ in the statement of Theorem 2, the result remains valid. To prove it we would construct $A$ in precisely the same manner. The important point is then that the comments immediately prior to Theorem 1 concerning the rigidity of the realization of lattice unique graphs remains valid. If in particular $B \subset \mathbb{R}^2$ satisfies that $U_A(A) \simeq U_A(A)$ via the isomorphism $\varphi : A \to B$, we may assume that $\varphi|_{\bigcup_{\theta \in \Theta}(H_k + t_\theta)}$ is the identity as in the proof above. The remaining part of the argument comparing the lengths of the beams then carries through unchanged. In conclusion, we are only left with the task of proving Theorem 1 for intersection graphs.

### 3 Intersection Graphs

In this section we prove Theorem 3. Consider two convex bodies $A$ and $B$. We are going to prove that if $I(A) = I(B)$, then for every graph $G \in C(A)$, there exists a graph $H_k(G) \in I(A)$ with properties as stated in the following lemma.

**Lemma 13.** Assume that $I(A) = I(B)$. For any $G \in C(A)$ and $k \geq 7$, there exists a graph $H_k(G) \in I(A)$ satisfying the following: Let $X \in \{A, B\}$. For any vertex $w$ of $G$, there is a corresponding vertex $s_0(w)$ of $H_k(G)$ with the following properties. Consider an arbitrary drawing of $H_k(G)$ as in intersection graph of $X$ and any two vertices $w, w'$ of $G$ and let $s_0 := s_0(w)$ and $s_0' := s_0(w')$. Then $\|s_0 s_0'\|_X \geq 4k - 18$. Furthermore, if $ww'$ is an edge of $G$, then $\|s_0 s_0'\|_X \leq 4k + 2$.

As is evident from the lemma, the vertices $(s_0(u))_{u \in V(G)}$, of any drawing of $H_k(G)$ as an intersection graph of $X$, are placed approximately as the vertices of a drawing of $G$ as a contact graph of scaled convex body $2kX$. To capture the uncertainty, we introduce the concept of $\varepsilon$-overlap graphs.
Definition 14 (\(\varepsilon\)-overlap Graph). Let \(\varepsilon > 0\) and \(A \subset \mathbb{R}^2\) be a symmetric convex body, and let \(v_1, \ldots, v_n \in \mathbb{R}^2\) be \(n\) points in the plane. Suppose that for any \(i, j \in [n]\), \(\|v_i - v_j\|_A \geq 2 - \varepsilon\). A graph \(G\) with vertex set \([n]\) and edge set satisfying \(E(G) \subseteq \{(i, j) \in [n]^2 \mid \|v_i - v_j\|_A \leq \varepsilon\}\) is called an \(\varepsilon\)-overlap graph of \(A\). We say that \(\{v_1, \ldots, v_n\}\) realize the graph \(G\) as an \(\varepsilon\)-overlap graph of \(A\). Further, we denote by \(C_\varepsilon(A)\) the set of graphs that can be realized as \(\varepsilon\)-overlap graphs of \(A\).

We next show how Lemma 13 leads to a proof of Theorem 3. First, the following lemma provides a reduction from \(\varepsilon\)-overlap graphs to contact graphs. The proof is a standard compactness argument and can be found in the full version of the paper.

Lemma 15. Let \(G_1 = (V, E_1)\) be a graph and \(A\) a convex body. If for every \(\varepsilon > 0\), it holds that \(G_1 \in C_\varepsilon(A)\), then there is a graph \(G_2 = (V, E_2) \in C(A)\) such that \(I_1 \subseteq E_2\).

The following lemma uses Lemma 13 to show that if \(I(A) = I(B)\), then any \(G \in C(A)\) is an \(\varepsilon\)-overlap graph of \(B\) for all \(\varepsilon > 0\).

Lemma 16. Assume that \(I(A) = I(B)\). For any \(G \in C(A)\), and any \(\varepsilon > 0\), \(G \in C_\varepsilon(B)\).

Proof. Write \(G = (V, E)\) and let \(k \geq 7\) be arbitrary. The assumption \(I(A) = I(B)\) in particular implies that \(H_k(G) \in I(B)\). Consider a drawing of \(H_k(G)\) as an intersection graph of \(B\) and define \(B := \left\{ \frac{x}{2k+1} \mid u \in V \right\}\). It follows from Lemma 13 that \(I(B)\) is a drawing of \(G\) as an \(\left(2 - \frac{4k-18}{2k+1}\right)\)-overlap graph of \(B\). Since \(\frac{4k-18}{2k+1} \geq 2 - 10/k\), it follows that \(G\) is an \(10/k\)-overlap graph of \(B\). As \(k \geq 7\) was arbitrary, the desired result follows.

Theorem 3 is an easy consequence of Lemma 15 and Lemma 16:

Proof of Theorem 3. Let the graph \(G \in C(A)\) have the properties of the theorem, i.e., for all \(H \in C(B)\), \(G\) is not isomorphic to a subgraph of \(H\). Suppose that \(I(A) = I(B)\). By Lemma 15 and 16, there is a graph \(H = (V, E') \in C(B)\) such that \(E' \subseteq E\), which is a contradiction.

It remains to prove Lemma 13. We will proceed to describe the construction of \(H_k(G)\) and provide several lemmas needed in order to prove that it satisfies the desired properties.

The proofs of these lemmas and of Lemma 13 are deferred to the full version of the paper.

For each vertex \(u \in V(G)\), we make a copy of a graph \(Q_k\) to be defined in the following. The vertices of \(H_k(G)\) will in turn be the union of the vertices of these copies. We will construct \(Q_k\) to have a designated vertex \(s_0\) and a cycle \(\alpha_k\) with the property that for every drawing of \(Q_k\) as an intersection graph of \(X \in \{A, B\}\), the cycle \(\alpha_k\) is contained in (and winds all the way around) the annulus \(\{x \in \mathbb{R}^2 \mid \|x\|_X \in (2k - 3, 2k)\}\). We may then informally view \(\alpha_k\) as an upscaled copy of \(X\) up to a slight imprecision that, compared to the size, decreases in \(k\). In order to construct \(Q_k\), we first define another graph \(P_k\) (which will be contained in \(Q_k\)) with a vertex \(s_0\) such that in every drawing of \(P_k\) as an intersection graph, \(s_0\) is contained in \(k\) nested disjoint cycles. A priori, it is not clear what it means for \(s_0\) to be contained in a cycle of the graph in every drawing, since the drawing is not necessarily a plane embedding of the graph. However, as the following lemma shows, it is well-defined if \(P_k\) is triangle-free. We believe the result to be well-known but have been unable to find the exact formulation that we require in the literature.

Lemma 17. If \(G\) is a triangle-free graph then every drawing of \(G\) as an intersection graph is a plane embedding.
Classifying Convex Bodies by Their Contact and Intersection Graphs

Proof. See the full version of the paper.

We are now ready to define $P_k \in I(A)$ for any $k > 0$. Besides being triangle-free, our aim is that $P_k$ should have the following properties:

1. There is a vertex $s_0$ such that in any drawing of $P_k$ as an intersection graph of $A$ and $B$, $s_0$ is contained in $k$ nested disjoint, simple cycles $\sigma_1, \ldots, \sigma_k$.
2. There is a path $\kappa_k$ from a vertex $s_k$ to a leaf $t_k$ such that in any drawing of $P_k$ as an intersection graph of $A$ or $B$, the path $\kappa_k$ is on the boundary of the outer face.

Construction 18 ($P_k$). See Figure 8. We define $P_k = I_A(A_k)$, where $A_k$ is a set of points to be defined inductively. Let $A_0 = \emptyset$ and $P_0 = I_A(A_0)$ be the trivial graph consisting of one vertex $s_0 = t_0$, which is also the path $\kappa_0$. Suppose now that $P_{k-1} = I_A(A_{k-1})$ has been defined. In order to define $P_k$, we first add vertices $a_k, b_k, s_k$ and edges such that $\tau_k := (a_k, t_{k-1}, b_k, s_k)$ is a 4-cycle. We now add vertices and edges that together with the path $a_k, s_k, b_k$ form a cycle $\sigma_k$. We make $\sigma_k$ so long that there exists a drawing as an intersection graph in which $P_{k-1}$ is contained in $\sigma_k$ with respect to both $A$ and $B$. We finish the construction of $P_k$ by adding vertices and edges that together with $s_k$ form a path $\kappa_k$ from $s_k$ to a vertex $t_k$, where $\kappa_k$ is so long that it cannot be contained in the cycle $\sigma_k$, neither as an intersection graph of $A$ nor $B$. (Note that a path of length $n$ contains $n/2$ independent vertices. A simple volume argument implies a bound on the number of independent vertices contained in the region enclosed by a cycle of a plane intersection embedding.) Let $A_k$ consist of $A_{k-1}$ together with all the added points.

Lemma 19. The graph $P_k$ has properties 1–2.

Proof. See the full version of the paper.

The most important property of $P_k$ is that every vertex $u \in \sigma_k$ has distance $\Omega(k)$ to $s_0$ in any drawing of $P_k$ as intersection graph of any $X \in \{A, B\}$ in the norm $\|\cdot\|_X$. This is exactly what we will use when constructing $Q_k$.

Lemma 20. Let $X \in \{A, B\}$. Consider any drawing of $P_k$ as an intersection graph of $X$. For any vertex $u \in \sigma_k$, we have $\|s_0 u\|_X > 2(k/9 - 1)$.

Proof. See the full version of the paper.

Having defined $P_k$ we are now ready for the construction of $Q_k$.

Construction 21 ($Q_k$). We here define a graph $Q_k \in I(A)$ by specifying a drawing of $Q_k$ as an intersection graph of $A$. Let $k' := 18(k + 1)$. We start with $P_{k'}$ and explain what to add to obtain $Q_k$. Let $u_0, \ldots, u_{n-1}$ be the vertices of $\sigma_{k'}$ in cyclic, counter-clockwise order. Consider an arbitrary drawing of $P_{k'}$ as an intersection graph of $A$ and a vertex $u_i$. Note that $d := \left\lceil \frac{\|u_{n-1}\|_A - \|u_i\|_A}{2} \right\rceil$ is the number of vertices needed to add in order to create a path from $s_0$ to $u_i$. It follows from Lemma 20 that $d \geq 2k$. 

![Figure 8](image-url)
We want to minimize the vector of these values \( d \) with respect to each vertex \( u_i \in \sigma_k \).
To be precise, we define
\[
(d_0, \ldots, d_{n-1}) := \min \left( \left\lfloor \frac{\|s_0u_0\|_A - 2}{2} \right\rfloor, \ldots, \left\lfloor \frac{\|s_0u_{n-1}\|_A - 2}{2} \right\rfloor \right),
\]
where the minimum is with respect to the lexicographical order and taken over all drawings of \( P_k \) as an intersection graph. Consider a drawing of \( P_k \) as an intersection graph realizing the minimum and let \( \mathcal{P} \) be the set of vertices in the drawing. For each vertex \( u_i \), we create a path \( \pi_i \) from \( s_0 \) to \( u_i \) as follows. Let \( v_i \) be the unit-vector in direction \( u_i - s_0 \). We add new vertices placed at the points \( v_i(j) := s_0 + 2jv_i \) for \( j \in \{1, \ldots, d_i\} \). We now define the vertices of \( Q_k \) as \( Q := \mathcal{P} \cup \bigcup_{i=0}^{n-1} \{v_i(1), \ldots, v_i(d_i)\} \) and define \( Q_k = I_A(Q) \). See Figure 9.

**Remark 22.** By construction, there exists a drawing of \( Q_k \) as an intersection graph of \( A \). If there does not exist one of \( B \), we are done, since we then clearly have that \( I(A) \neq I(B) \).
Now suppose that there exists a drawing of \( P_k \) as an intersection graph of \( B \) such that
\[
\left( \left\lfloor \frac{\|s_0u_0\|_B - 2}{2} \right\rfloor, \ldots, \left\lfloor \frac{\|s_0u_{n-1}\|_B - 2}{2} \right\rfloor \right) < (d_0, \ldots, d_{n-1}),
\]
where \( < \) denotes the lexicographical order. We can now define a graph \( Q_k^B \in I(B) \) from \( P_k \) in a similar way as we defined \( Q_k \) by adding \( \left\lfloor \frac{\|s_0u_i\|_B - 2}{2} \right\rfloor \) vertices to form a path from \( s_0 \) to each \( u_i \). It then follows from (3) that \( Q_k^B \not\in I(A) \), so in this case we have likewise succeeded in proving \( I(A) \neq I(B) \). In the following, we therefore assume that \( Q_k \in I(B) \) for any \( k \) and that no drawing of \( P_k \) as an intersection graph of \( B \) satisfying (3) exists.

First we need to show that \( Q_k \) contains a cycle \( \alpha_k \) as described earlier.

**Lemma 23.** The set of edges of \( Q_k \) contains the pairs \( v_i(j)v_{i+1}(j) \) for any \( i \in [n] \) and \( j \in \{1, \ldots, k\} \), and for each \( j \in \{1, \ldots, k\} \), these edges thus form a cycle \( \alpha_j \). In the specific drawing of \( Q_k \) as an intersection graph defined in Construction 21, the cycle \( \alpha_j \) is contained in the annulus \( \{x \in \mathbb{R}^2 \mid \|s_0x\|_A \in [2j - 1, 2j]\} \).

**Proof.** See the full version of the paper.

The above lemma shows that the cycle \( \alpha_k \) behaves nicely in one particular drawing of \( Q_k \) as an intersection graph. To see that something similar holds for every drawing, we refer the reader to the full version.

We now provide the definition of the graph \( H_k(G) \), as mentioned in the beginning of this section.
The following lemma characterizes some of the edges of $H_k(G)$ and will be crucial in the proof of Lemma 13.

> **Lemma 25.** Consider two vertices $w, w'$ of a drawing of a graph $G$ as a contact graph. Denote by $Q$ and $Q'$ the copies of $Q_k$ in $H_k(G)$ corresponding to $w$ and $w'$, respectively, such that $s_0, \pi, \alpha_j, v_i(j)$ denote objects in $Q$ and $s'_0, \pi', \alpha'_j, v'_i(j)$ denote objects in $Q'$. If $v_i(j)v'_i(j')$ is an edge of $H_k(G)$, then $j + j' \geq 2k - 4$.

If $ww'$ is an edge of $G$, then there is an edge $v_i(k)v'_i(k)$ in $H_k(G)$.

**Proof.** See the full version of the paper.

As mentioned, the final proof of Lemma 13 is deferred to the full version, but we can now provide the main ideas. We first need to prove that in any drawing of $Q_k$ as an intersection graph with respect to $X \in \{A, B\}$, any cycle $\alpha_j$ is contained in an annulus only slightly wider than as stated in Lemma 23. Furthermore, $\alpha_j$ winds around $s_0$ in the sense that if we trace the full curve $\alpha_j$, the change of argument with respect to $s_0$ will be $\pm 2\pi$. To prove the lower bound $\|s_0s'_0\|_X \geq 4k - 18$ in Lemma 13, we exclude that the distance is smaller by dividing into two cases depending on the actual distance. Figure 10 depicts the two cases for each of which we prove that there would be an edge in $H_k(G)$ violating Lemma 25. The upper bound $\|s_0s'_0\|_X \leq 4k + 2$ when $ww'$ is an edge of $G$ is likewise an easy consequence of Lemma 25, as otherwise, an edge $v_i(k)v'_i(k)$ would be missing from $H_k(G)$.

### 4 Concluding remarks

It is natural to investigate the special case of convex bodies with the URTC property. Here our proof of Theorem 2 fails since the hexagons are not rigid structures. Together with Konrad Swanepoel, we have promising progress in generalizing Theorem 1 to also handle this case.

Another interesting direction is to consider convex bodies in three and higher dimensions. Already in three dimensions, it appears to be very difficult to characterize when two bodies induce the same graph classes.

#### References


