Algorithm:

Given:
- S a set of data-points with n points of d_s dimensionality
- ε the minimum distance to be considered density reachable
- minPts the minimum ε-reachable neighbors to make a core point
- t, a threshold cluster size to divide noise from correct data
- d_t a target dimensionality for S

1. Train and deploy an autoencoder to generate set S' from S with n points of dimensionality d_t. Ignore this step is $d_s = d_t$.

2. For each s in S' append the label l which is observed for s to create S" with n points of dimensionality d_t+1.

3. Apply DBScan(ε, minPts) to S" to generate C, a set of clusters observed in S".

4. Add all points in C_o to M, a set of mislabeled point indexes from S.

5. For all remaining c in C, add all indexes in c to M if $|c| < t$.

6. Return M.