The Algorithm

Core Point
A point is a core point if it has **at least** *minpts* neighbors within *eps* distance of itself.
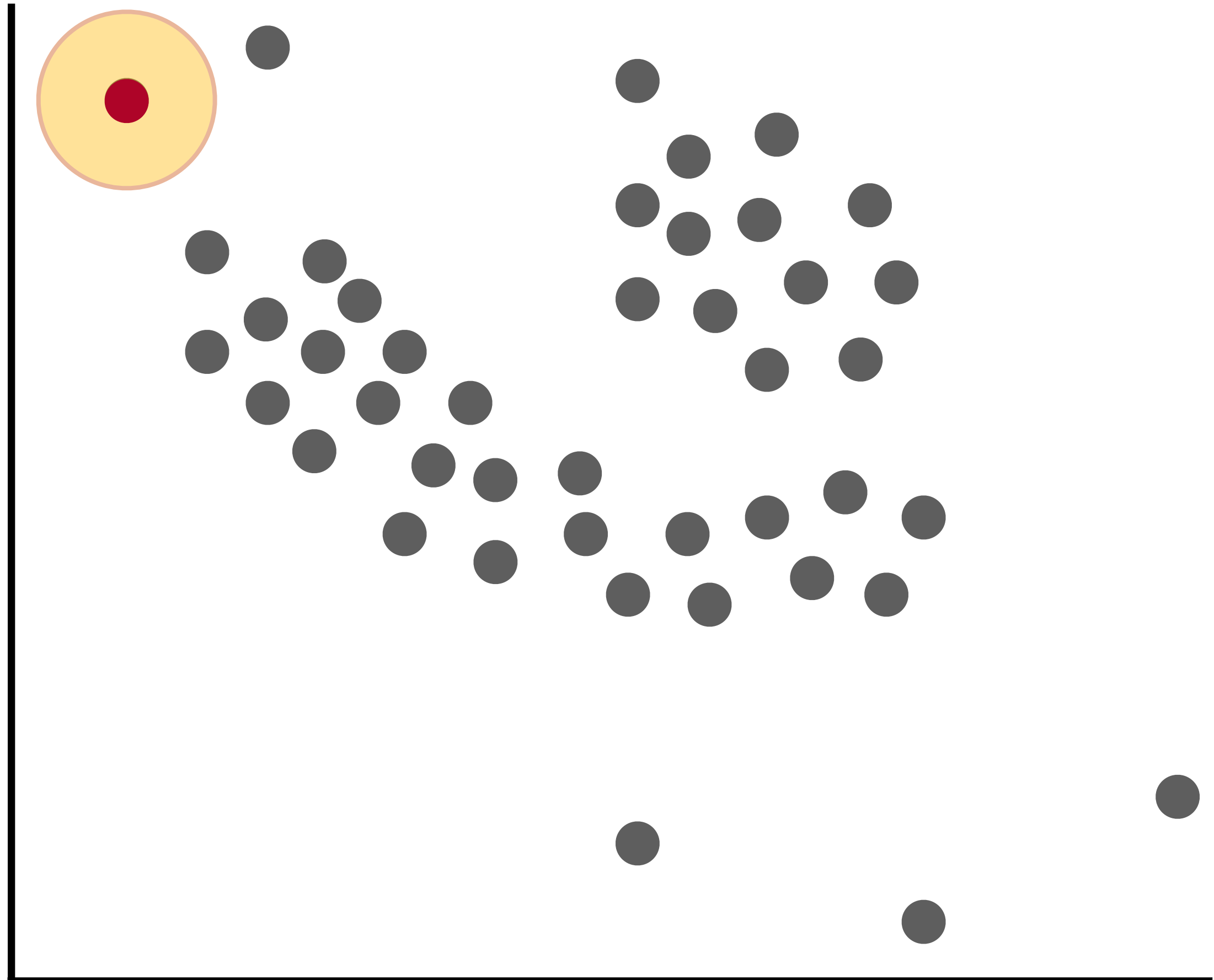
Border Point
A point **without** at least *minpts* neighbors within *eps* distance of itself, **but** is a neighbor of a core point.

Noise
A point **without** at least *minpts* neighbors within *eps* distance of itself, **and is not a** neighbor of a core point.

The Algorithm

Directly density reachable
Point A is directly density reachable from a core-point B if it is in the neighborhood of B.