

# Dynamic Time-Dependent Routing in Road Networks Through Sampling

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# Abstract

The earliest arrival in road networks with:

- TIME DEPENDENT functions
- DYNAMIC UPDATES
- It compute with SMALL ERROR
- Doesn't suffer from MEMORY LACK on large instances
- This algorithm is the only that is able to answer to queries below 50 ML

# Introduction

The road network is a weighted graph, directed graph :

**Nodes**: positions

**Edges** : road segments

**Weight** : travel time a car need to traverse the road segments .

**A common assumption** : travel times are time independent

**Result**: problem will be a classical shortest path problem

**Problem** : road networks are huge and Dijkstra algorithm is slow!

## Out line

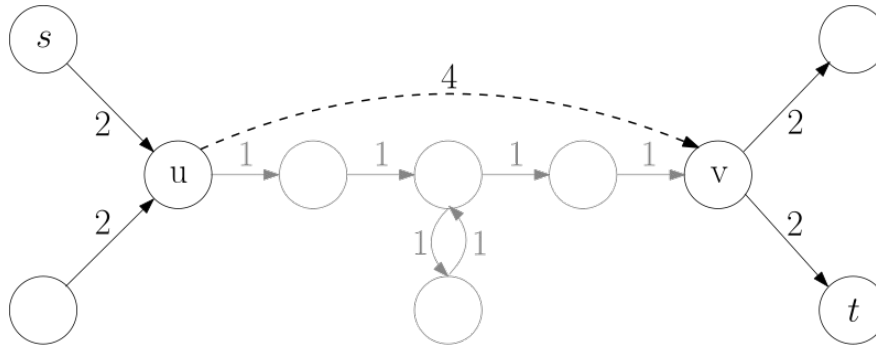
They start by describing a baseline that call the free flow heuristic.

Then build on it and introduce Their algorithms TD-S and the profile extension TD-S+P and dynamic extension TD-S+D

# contraction Hierarchies

we can use CH in pre processing step

Contraction hierarchies (CHs) are a well-known algorithm for fast and exact route planning on road networks



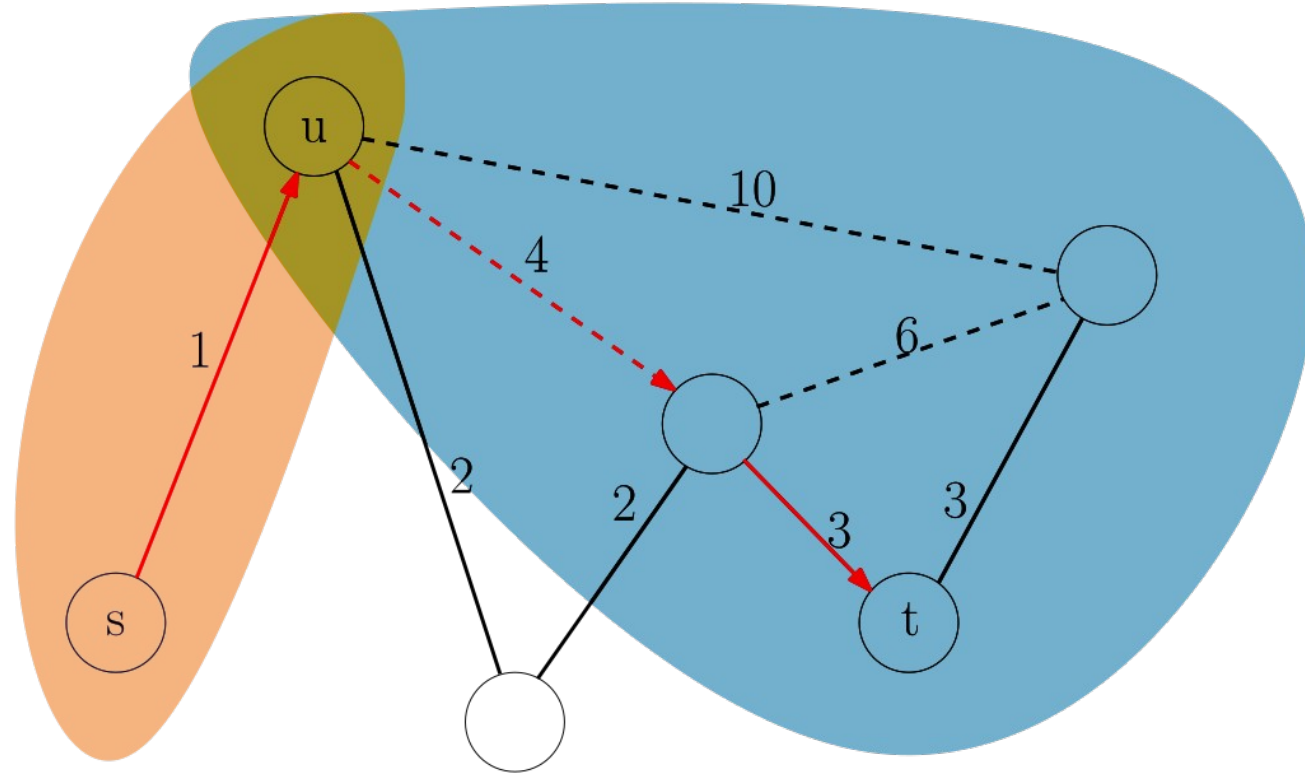
To find a path from s to t the algorithm can skip over the Grey vertices and use the dashed shortcut instead. This reduces the number of vertices the algorithm has to look at.

### contraction Hierarchies:

- road networks are highly hierarchical. for example highway , are "more important" and higher up in the hierarchy than for example a junction leading into a dead end. the algorithm doesn't have to consider the full path at query time.

The higher is the node the later  
it is contracted.  
we first contract the least  
important node.

## Overview on contraction Hierarchies



# Customized contraction hierarchies- CCH

If the edge weights are changed more often like dynamic time, **CH can be extended** to a three-phase approach by including a customization phase between the pre processing and query phase.

- In the pre processing phase, most of the run time is spent on **computing the order** in which the nodes are contracted
- This sequence of contraction operations can be **saved** for when they are later needed in the customization phase
- depending on the **new edge weights** it may be necessary to **recompute** some shortcuts.



## Computing Errors

When taking predicted congestion into account, many proposed algorithms compute paths with an error

Let **d** denote the length of the computed path and **dopt** the length of a shortest path

Absolute error:  $|d - \text{dopt}|$

Relative error :  $|d - \text{dopt}| / \text{dopt}.$

# Computing Errors

Unfortunately, the predictions do not quantify **uncertainties**, and uncertainty is huge: The time a typical German traffic light needs to cycle through its program is between 30s and 120s and Traffic lights often adapt to the actual real time traffic.

# PROBLEM DEFINITION

The input of earliest problem:

NODES  $>$  S AND T

Departure time  $>$  s

The task is consist of computing **ST- path with minimum arrival time.**

We want a routing system that accounts for **predicted and real time congestion**  
(dynamic time dependent routing )

**TD: Free Flow Heuristic:** A solution to time-independent routing problem

**TD-S :** Solve the earliest arrival problem with **predicted congestion**

**TD-S+P :** solve **profile** problem

**TD-S+D:** take **real time congestion** into account

The free flow travel time along an edge is the minimum travel time over the whole day.

## TD routing algorithm : Free flow Heuristic

**assumption**

No Congestion  
(time-independent)

The min value of  $e$ 's travel  
time function  
of  $f_e$

**Step**

Find the **shortest**  
time independent  
path  $H$

Compute **time dependent**  
travel time along  
 $H$  given departure time (sampling)

The first step can be fasten using any time independent speed up: such as CH

**Avg flow heuristic** : the same but it use average travel time

# The Simplest TD Routing Algorithm: The Free flow Heuristic

Free flow never reroutes based on the current traffic situation

The main problem with it is that the computed paths can potentially differ significantly from the optimal ones.

The computed solutions can have a significant error.

# The Algorithm : TD-S

- |   |   |
|---|---|
| 1 | Fix a small set of time intervals called time windows.<br>Better $k \leq 10$        |
| 2 | For each time window and edge compute the <b>average travel time</b> in that window |
| 3 | For Each time window make a <b>time-independent graph</b> .                         |

It s time independent  
Because we calculate avg

Pre process each of these graphs using your favorite time-independent speedup technique

IN STEP 2, THEY USE A SAMPLING APPROACH,  
AVG THE TIME DEPENDENT TRAVEL TIME WITHIN EACH INTERVAL  
FOR EX: 7:10, 7:15 , 7:50

# The query phase of TD-S

1

For every graph they compute  
a shortest time independent path  
St-path and mark the edges in the path.

They use Dijkstra here !

2

search several times for departure  
times at regular intervals

## Computing profile: TD-S+P

The algorithm is fast because they only have to mark the edges once per query then run the time-dependent search numerous times.

For a sampling rate of 10min, the algorithm would mark the edges as for TD-S, then run the time-dependent extension of Dijkstra's algorithm restricted to the marked edges with the departure times 0:00, 0:10, 0:20...23:50



# TD-S+P

## Dynamic TD-Routing Through Sampling

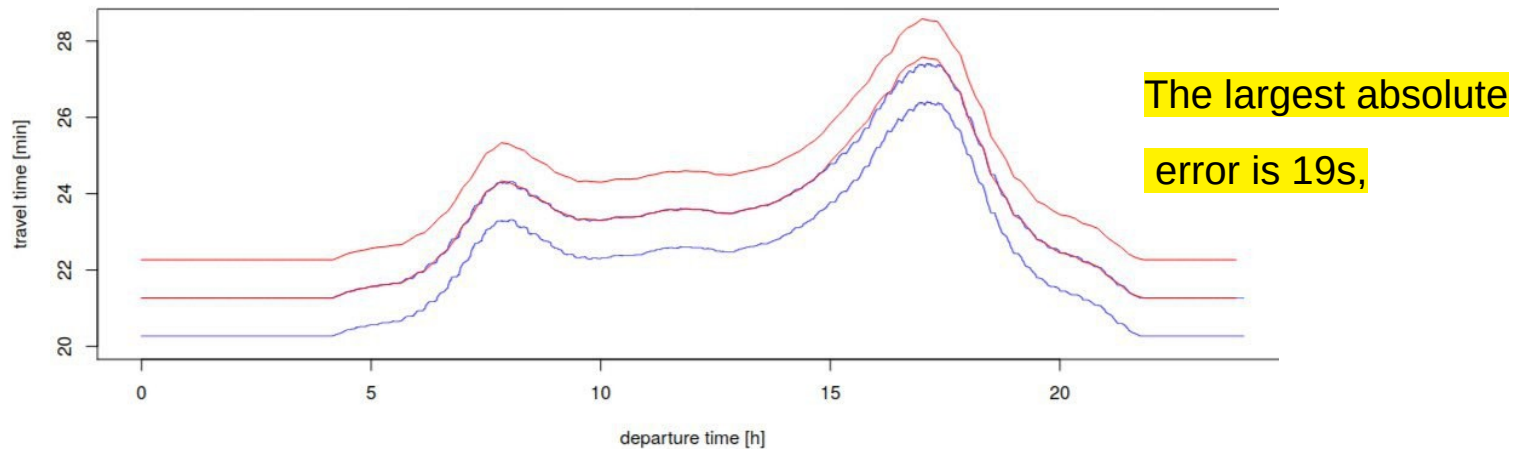


Figure 2

Example profile over 24h. The red curve (top) was computed with TD-S+P, while the blue one (bottom) is the exact solution. The middle overlapping curves are the actual profiles. To improve readability

# TD-S+D

However, in many applications we must also take real time congestion into account.

Adapting TD-S by **modifying the computation of the sub graph H** yielding TD-S+D.

# TD-S+D

The sub graph  $H$  is the union of  $k$  paths

TD-S+D adds a shortest  $st$ -path according to the current real time traffic as  $k+1$ -th path to the union.

A efficient solution to the routing problem with real time congestion is needed.

# TD-S+D

In the pre processing step, TD-S+D computes one CCH in addition to the  $k$  CHs of TD-S.

At regular time intervals, such as every 10s, TD-S+D updates the CCH edge weights to reflect the real time traffic situation

## Simulating Traffic

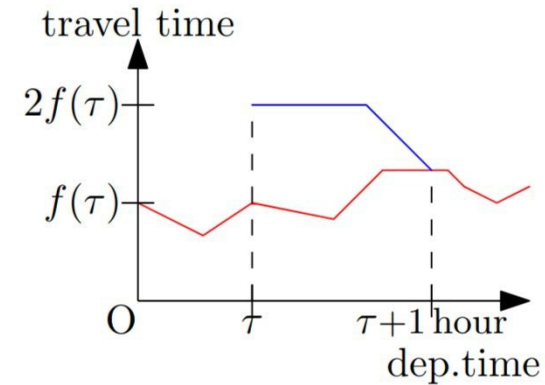
Unfortunately, they do not have access to good measured real time traffic. they **simulate real time congestion** to study the performance of TD-S+D

# Simulating Traffic

- For an earliest arrival time query from  $s$  to  $t$  with departure time  $\tau$ , they **first compute the shortest time-dependent path  $P$**  with respect to the historic travel times
- On path  $P$  they **generate three traffic congestion** by picking three random start edges.
- **From each of these edges they follow  $P$  for 4min**, yielding three sub paths

# Simulating Traffic

- 1- Travel time function  $f$  of  $e$
- 2- by doubling the travel time at  $f(\tau)$  and assume that it remains constant for some time
- 3- The congestion should be gone at  $\tau + 1$ h.
- 4- FIFO-property:  $e$  modified function must have slope of -1 before  $\tau + 1$  before joining the predicted travel time



The number of exactly solved queries decreases with instance size as the paths lengths grow with size

as most queries are answered exactly with TD-S

TD-S+4 has larger errors as it uses fewer time windows.

**Table 2** Number of exact time-dependent queries and absolute and relative errors for Freeflow, TD-S+4, and TD-S+9. “Q99” refers to the 99%-quantile and “Q99.9” the 99.9%-quantile.

Graph	Algo	Exact [%]	Relative Error [%]				Absolute Error [s]			
			Avg	Q99	Q99.9	Max	Avg	Q99	Q99.9	Max
Lux	Freeflow	80.0	0.244	5.1	11.5	28.1	5.0	106	235	356
Lux	Avgflow	81.0	0.123	2.5	6.4	19.4	2.5	49	143	329
Lux	TD-S+4	97.7	0.008	0.2	1.5	4.9	0.2	4	30	141
Lux	TD-S+9	99.6	<0.001	0.0	0.1	1.7	<0.1	0	3	27
Ger	Freeflow	67.9	0.085	1.5	3.1	12.4	11.1	200	417	825
Ger	Avgflow	69.2	0.044	0.8	1.9	10.3	5.9	113	284	587
Ger	TD-S+4	94.6	0.005	0.1	1.0	3.0	0.8	17	159	474
Ger	TD-S+9	98.2	0.001	<0.1	0.4	3.0	0.3	1	76	374
OGer	Freeflow	60.7	0.140	2.0	4.7	12.4	15.9	219	465	1 104
OGer	Avgflow	68.8	0.050	0.9	2.2	6.5	5.7	96	227	619
OGer	TD-S+4	96.4	0.002	0.1	0.4	2.0	0.3	6	47	333
OGer	TD-S+9	98.5	0.001	<0.1	0.2	2.0	0.1	1	24	276
CEur	Freeflow	54.9	0.089	1.4	2.7	10.8	26.4	428	833	1 477
CEur	Avgflow	55.8	0.048	0.8	1.7	6.6	14.2	235	507	1 069
CEur	TD-S+4	91.1	0.006	0.2	0.7	3.8	1.8	47	226	547
CEur	TD-S+9	96.8	0.001	<0.1	0.3	1.2	0.5	6	109	397



# Analysis

TD-S with two selections of time windows:

TD-S+4 uses the windows 0:00–5:00, 6:00–9:00, 11:00–14:00, and 16:00–19:0

TD-S+9 uses the windows 0:00–4:00, 5:50–6:10, 6:50–7:10, 7:50– 8:10,  
10:00–12:00, 12:00–14:00, 16:00–17:00, 17:00–18:00

the query running times  
and the memory of TD-  
S+4 are lower.

TCH is lacking from  
memory .they couldn't  
run on 128 gig

TD-S+4 only needs about  
2.4 times the memory  
required by the input.

TD-S+9 needs 4.1 times  
the memory.

TD-S+4 has lower  
pre processing time  
than TCH

■ **Table 3** Average preprocessing and running times and memory consumption of various algorithms.

Graph	TD-Dijkstra	Freeflow	Avgflow	TD-S+4	TD-S+9	TCH
Average Query Running Time [ms]						
Lux	4	0.02	0.02	0.11	0.26	0.18
Ger	1 116	0.19	0.20	0.99	3.28	1.81
OGer	813	0.12	0.14	0.97	2.09	1.12
CEur	4 440	0.42	0.29	3.83	6.85	OOM
Max. Query Memory [MiB]						
Lux	13	17	17	29	47	328
Ger	1 550	2 132	2 130	3 630	6 127	42 857
OGer	461	855	854	1 880	3 589	8 153
CEur	4 980	7 058	7 053	12 411	21 336	>131 072
Total Preprocessing Running Time [min]						
Lux	—	<0.1	<0.1	<0.1	0.1	0.6
Ger	—	1.6	2.2	7.6	14.7	86.2
OGer	—	1.5	1.6	5.9	16.4	26.8
CEur	—	8.6	8.1	33.9	70.7	381.4

# Dynamic Time-Dependent Routing

In the dynamic scenario, we consider two types of congestion:

- (a) the predicted congestion.
- (b) the real time congestion.

The Predicted Path heuristic (Predict. P) as baseline, TD-S+D4, and TD- S+D9.

The Predicted Path heuristic computes a shortest path P with respect to only the predicted congestion NOT REAL TIME CONGESTION

P then is then evaluated with respect to both congestion types TD-S+D4, and TD-S+D9.

## Predicted Path P

Free flow and Predicted Path are similar in spirit.

Free flow solves the time-dependent routing problem by **ignoring predicted congestion**.

Similarly, Predicted Path solves the dynamic time-dependent routing problem by **ignoring real time congestion**.

The Free flow heuristic produces surprisingly small errors

On the Luxembourg instance only **1.6%** of the queries are solved optimally.

TD-S+D reduces these errors.

The minimum number of optimally solved queries is **92.9%**.

Graph	Algo	Exact [%]	Relative Error [%]				Absolute Error [s]			
			Avg	Q99	Q99.9	Max	Avg	Q99	Q99.9	Max
Lux	Predict.P	1.6	17.228	56.1	75.0	93.8	323.0	739	826	997
Lux	TD-S+D4	94.7	0.017	0.5	2.3	6.2	0.6	15	93	231
Lux	TD-S+D9	95.0	0.016	0.5	2.2	6.2	0.5	14	89	231
Ger	Predict.P	55.1	1.2	17.9	36.9	79.3	78.5	552	741	1001
Ger	TD-S+D4	90.9	0.032	1.0	2.6	7.0	3.5	116	233	474
Ger	TD-S+D9	93.4	0.026	0.9	2.5	6.2	2.8	99	216	469
OGer	Predict.P	52.3	1.352	18.7	38.3	65.8	84.9	563	738	934
OGer	TD-S+D4	91.5	0.031	1.0	2.6	5.4	3.2	108	224	462
OGer	TD-S+D9	92.9	0.028	0.9	2.5	5.4	2.9	102	219	462
CEur	Predict.P	72.6	0.392	7.0	25.9	81.9	41.0	443	653	1870
CEur	TD-S+D4	89.5	0.015	0.5	1.6	5.2	3.3	106	244	547
CEur	TD-S+D9	94.0	0.011	0.3	1.4	5.2	1.9	69	205	397

Number of exact dynamic, time-dependent queries and absolute and relative errors for the predicted path, TD-S+D4, and TD-S+D9.

■ **Table 7** Comparison of earliest arrival query algorithms. “n/r” = not reported. We report the running times as published in the corresponding papers (ori) and scaled by processor clock speed.

	Numbers from		Link & Merge?	Relative Error [%]			Run T. [ms]	
				avg.	Q99.9	max.	ori	scaled
TDCALT-K1.00	[10]	OGer	●	0	0	0	5.36	3.77
TDCALT-K1.15	[10]	OGer	●	0.051	n/r	13.84	1.87	1.31
eco SHARC	[8]	OGer	●	0	0	0	25.06	19.7
eco L-SHARC	[8]	OGer	●	0	0	0	6.31	5.0
heu SHARC	[8]	OGer	●	n/r	n/r	0.61	0.69	0.54
heu L-SHARC	[8]	OGer	●	n/r	n/r	0.61	0.38	0.30
TCH	Tab. 3	OGer	●	0	0	0	1.12	
TDCRP (0.1)	[6]	OGer	●	0.05	n/r	0.25	1.92	
TDCRP (1.0)	[6]	OGer	●	0.68	n/r	2.85	1.66	
Freeflow	Tab. 2 & 3	OGer	○	0.140	4.7	12.4	0.12	
Avgflow	Tab. 2 & 3	OGer	○	0.050	2.2	6.5	0.14	
FLAT- $SR_{2000}$	[22]	OGer	○	1.444	n/r	$n/r^3$	1.28	1.18
CFLAT-BC3K+R1K,N=6	[23]	OGer	○	0.031	n/r	19.154	4.10	4.73
TD-S+4	Tab. 2 & 3	OGer	○	0.002	0.4	2.0	0.97	
TD-S+9	Tab. 2 & 3	OGer	○	0.001	0.2	2.0	2.09	

A\*  
CONTRACTION  
ARC-FLAGS  
LINK AND MERGE  
+ Large memory

51 GB  
16.1 GB  
1.8 GB

# Conclusion

Introducing TD-S, a simple and efficient solution to the earliest arrival problem with predicted congestion on road graphs.

We extend it to TD-S+P which is the only algorithm to solve the profile variant in at most **50ms** on all test instances.

Further, we demonstrated with TD-S+D that additional real time congestion can easily be incorporated into TD-S.