**INTRODUTION**

With the rapid advance of sensing, communication, and mobile computing, mobile crowd-sensing [1] has become a paradigm attached much attention for gathering distribute sensory data to share with the general public. With the help of mobile crowd-sensing the cost of many data collection and dissemination tasks over wide range of region can be significantly reduced. Being carried by human user who locate in different place, smartphone can easily collect ubiquitous data and share such data with a large number of potential users [2], [3]. The vehicle-based mobile crowd-sensing with similar mobility, distribution in large is evolving rapidly. Equipped with onboard sensors such as GPS, video cameras and communication module and so on, a vehicle also can become a powerful crowd-sensing application like as a smartphone to collect data and execute a various of sensing task, including traffic monitoring [4][5], environment monitoring [6],urban Wi-Fi characterization [7], etc.

A vehicle-based mobile crowd-sensing system typically composed of two parts: cloud management platform (CMP) and mobile vehicles embedded with crowd sensing application. An example of vehicle-based crowd-sensing is shown in figure 1. The cloud management platform is responsible for selecting a set of vehicles to participate in urban crowd sensing task and processing perceives data which forwarded from vehicles to provide data services to user. Once a vehicle receives authorization of CMP, it will gather the required data and then upload to CMP. This indicates that a vehicle-based mobile crowd sensing-system with widespread geographical distribution of vehicles is capable of supporting a wide range of large-scale monitoring [8].

Generally, it is greatly important to select vehicles to participate in collaborative sensing, which manifest the success of vehicle-based mobile crowd-sensing. Consider an extreme case that the CMP recruit all vehicles to execute crowd-sensing task, apparently, it can perceive the surroundings and achieve what it is assigned to do, but multiple vehicles in the same region at the same time will introduce data redundancy due to a single vehicle is sufficient to cover a geographical region, which application should avoid. Therefore, the vehicle usually receive credit or non-monetary reward from CMP [9]-[11]and the CMP with constraint budget, and selects a set of vehicle from all vehicles under operation that best satisfy with the user’s requirements for better crowd-sensing quality[11].



Figure 1. An example of vehicle-based crowd-sensing application. Buses embedded with plentiful sensors are distributed over a large city. Cloud management platform assign sensing task to the recruited vehicle which can contribute to the sensing tasks by returning their sensed data to CMP. And then CMP processes the received data to provide to user.

The location of vehicles make a greatly influence on the quality of vehicle-based mobile crowd-sensing [12], because of the CMP assigns crowd-sensing tasks to vehicles that operates in different regions. As mentioned above, vehicles within same region introduces redundancy, this case is we try to avoid. There is another worst case where no vehicles are operating in the regions of interest at a specific time resulting in blank data. Obviously, the quality of crowd-sensing is sensitive to space and time, so the spatial-temporal coverage is a fundamental metric of the vehicle-based mobile crowd-sensing quality. Particularly, spatial-temporal coverage intends to cover as many regions of interest as possible and make sure all areas is covered at least once for a period of time. In reality, we are supposed to be aware that the spatial-temporal coverage of sensing data of vehicle-based mobile crowd-sensing is more dynamic on account of each vehicle keeps moving persistently across the city as his own schedule.

However, public transport buses, which is distinct from taxi or private car without operating plans, strictly periodically follow an explicit timetable made by bus company. Hence the location of each bus is predictable in spite of the highly dynamic mobility, which opens up a new opportunities to achieve high quality crowd-sensing with less budget for CMP. Because each bus is able to cover many areas for a period of time. For another, taking into consideration the future location of vehicles can effective prevent the quality of crowd-sensing from affecting for high mobility instead of only depend on current location as smartphone-based crowd-sensing do[13]. In the next, a vehicle refer more politically to be a bus.

In this paper, we concentrate on how to achieve a high quality of crowd-sensing making full use of the predictable location of buses with limited budget. After an analysis on the relations between spatial-temporal coverage and the location of vehicle, we formulate the problem of selection vehicle (SV) for maximizing the spatial-temporal coverage of city with constraint budget. Through thoroughly proof, we find that SV is NP-hard. And we design a truthful and efficient approximation algorithm, called ECQA, to select a set of vehicle from all candidates under operation with a high efficiency (minimal budget and maximizing spatial-temporal coverage), which can approximate the optimal solution within a guarantee performance no less than , with polynomial-time computation complexity. We also theoretically prove the ECQA guarantee is truthfulness.

**SYSTEM MODEL AND PROBLEM FORMULATION**

**A. System Model**

We consider a vehicle-based crowd-sensing system consisting of a CMP and many vehicles embedded with substantial sensors. The CMP periodically propagates sensing tasks to be completed by running vehicle.

In a city area, we divide road into a serial of small segments. As an example shows in figure 2. Let denote the set of all small segments, . When the CMP broadcasts a crowd-sensing task to be finished for a period of time, i.e. T. Supposed the time is discrete, so we can assume .The distribution of vehicle is large-scale, each vehicle equipped with the sensor module that we has designed in [14] is able to join crowd-sensing tasks. Assume there are n vehicles can perform sensing assignments and the set of vehicles is denoted by . Initially, the CMP predicts the current position of all vehicles according to the timetable and broadcast the data packet until receive the ACK, if the prediction is not consistent with the actual current location obtained through Global Positioning System (GPS) [15] employed in vehicle, it will be updated, respectively. With the initial location of vehicles and scheduled timetable, we can get the location of a vehicle at a specific time , which is denoted by . Thus the trajectory of n vehicles can be represented as follows:

(1)

, where the size of is .

In practice, we are not anticipate that all vehicles are involved in crowd-sensing due to it will introduce redundancy. For example, in terms with traffic monitoring, nearby vehicles usual upload the same traffic information, which ought to avoid. Therefore, we regular that a vehicle who is selected to take part in crowd-sensing will gain a reward paid by CMP and the budget of CMP is limited and no morn than Next, we define the sensing reward.

**Definition 1: Sensing Reward (SR)** a vehicle is selected to complete crowd-sensing task often associated with a reward paid by CMP. Let denote the reward to . Then, the reward vector for all vehicles is:

(2)

With the constraint of budget of CMP, not all vehicles participate in crowd-sensing, we utilize an indication vector to imply whether a vehicle is selected or not,

(3)

, where is the set of chosen vehicles. Let be the total reward to buses in, which can be computed as,

(4)

As mentioned, the quality of crowd-sensing is related with spatial-temporal coverage, which means to cover as many regions of interest as possible and ensure each road segment to be covered once at least within a sensing time T. Let we introduce the notion of spatial-temporal coverage.

**Definition 2: Spatial-temporal Coverage (STC)** determines the quality of crowd-sensing. Formally, which can be defined as:

(5)

Next, we show an example to explain the implication of STC. In figure 2, the scheduled trajectory of Bus 1, Bus 2, Bus 3, Bus 4 is {BC, BE, DE, AD}, {EF, BE, AB}, {HI, HD, AD, AB, BC},{AD, AB, BE, EH, DH}, respectively. In a period time , the location of Bus 1 to Bus 4 is { BE, AD, DE, BE}, {EF, AB, EF },{HI, AD, AB, BC}, {AB, BE, EH ,DH}, respectively. From equality (1), we get that,

(6)

If the CMP with budget limited is capable of selecting two vehicles to participate crowd-sensing, then we consider two cases as bellows,

(7)

(8)

It can be seen that the set of {Bus1, Bus 2} have covered six different place in space and the segment of {EF} has been covered twice over time. On the contrary, the set of {Bus1, Bus 3} simply have covered six different place in space, so we are more willing to select {Bus 1, Bus 2} to participate in crowd-sensing.



Figure 2. An example shows that we divide the city area into small fragments, such as R = {AB, AD, BC, BE, DE, EF, EH, DH, HI}, where R is the city area.

**B. Problem Statement**

In a region of interest, each vehicle equipped with amount of sensors which continuously sense the surrounding environment as it passes. However, at a specific moment, if all vehicles within a same road segment are involved in crowd-sensing, it will lead to overlap coverage. Thus it is highly demand to select an appropriate set to finish the crowd-sensing tasks and ensure the quality of crowd-sensing. Based on the system model, we are ready to formally define the problem of optimal selection of vehicle (SV) for maximizing the spatial-temporal coverage with SR budget constraint.

**Definition 3: SV Problem (SVP)** is to determine a set of vehicle under the budget constraint with the objective of maximizing the spatial-temporal coverage.

. (9)

Actually, the sensing data at different road segment and at a different period time may have varying importance degree, such as we are more interested in hotspot with high traffic flow in the morning rush hour. For this reason, we introduce priority power to indicate the relative importance of each road segment where the higher priority a vehicle is more likely to be selected to join in crowd-sensing. Through analyzing historical data, it is easy to acquire traffic performance index (TPI) of each road segment. Let denote the TPI of at a specific time , which is assumed known and normalized between 0 and 1, e.g. . With the TPI we define priority power.

**Definition 4: Priority Power (PP)** is the importance of a road segment in a crowd-sensing period time, which is a function of defined as . So , thus the first order derivative of satisfies:

(10)

Therefore, priority power is expressed as follows:

(11)

With the priority power, the STC can be redefined as,

(12)

, so the SVP can be rewritten as,

. (13)

We hope that the solution of SVP can be found with a time efficient, unfortunately, it is NP-hard even though the trace of vehicles is predictable. In the next, we are going to prove SVP is NP-hard and propose an improved approximation algorithm based on greedy to solve the SVP.

**SOLUTION TO THE SVP**

**A. Complexity Analysis of SVP**

**Theorem 1.** The SVP is NP-hard even though the trajectory of all vehicles are predictable.

Proof: To prove the NP-hard property of SVP, we should demonstrate it belongs to NP firstly, and then find another NP-hard problem proven that could be reduced to it. Assuming there is a possible solution , it is clearly that the correctness of this solution can be certified in polynomial, the time complexity of the checking algorithm is , which means SVP is NP. Next, we use an instance of budget maximum coverage problem as the known NP-hard, which is defined as follow. Given a collection of sets, each set has a cost and an element in associated with a weight .The question is whether we can find a subset that the total cost is not more than a given budge L and the total weight of elements in is maximized. Obviously, each set can be mapped to , , be equivalent to , and weight of each element in R is mapped to the priority power, of each vehicle in V. We have mapped the formulation of SVP to budget maximum coverage problem. And then we can see that a solution of budget maximum coverage problem is also the solution of SVP. So SVP is NP-hard.

Consequently, to achieve a truthful and computationally efficient crowd-sensing system, it is highly demand to propose an approximate algorithm for solving SVP.

**B. Approximate Algorithm to Solve SVP**

We have analyzed the NP-hardness of SVP, it becomes computationally impracticable to select an optimal set of vehicles from all the candidate vehicles when the number of candidate vehicles is huge. As for a metropolis like Beijing, the number of vehicles under operations is about 30,000 by the end of 2016 [16]. To achieve the desired computational efficiency, we propose an approximate algorithm called efficient combination query algorithm (ECQA) to solve SVP. While designing the algorithm, not only should we consider to select a vehicle with maximized STC, but also ask for less reward from CMP with budget constraint. Therefore we define the reward efficient.

**Definition 5: Reward Efficient (RE)** indicates the marginal STC achieve per unit reward.

The ECQA adopts a greedy strategy to solve the problem. The greedy policy is to select the next most reward effectiveness vehicle, which means to select a vehicle maximized marginal STC per unit reward, until the total SR exceed the budget of CMP. Mathematically, the reward-efficient for selecting a vehicle can be computed as follows:

(14)

The algorithm tries many rounds, a best vehicle with maximum RE is determined as a result of each round. In equation (14), where denotes the reward efficient of vehicle , is solution obtained from , , and . The algorithm will not terminate until the budget constraint is active. The pseudo-code is listed in table 1.

**Table 1. The pseudo-code of ECQA**

|  |
| --- |
| Approximate Algorithm for SVP |
| Input: set of vehicle under operation, set sensing reward of each vehicle, the budget constraint of CMP, an initial set of cardinality is an integer as 3, assume the schedule time of each vehicle is known.  Output: set is the best set of vehicle selected by ECQA |
| Procedure:   1. Initialization 2. ; 3. for each 4. ; 5. for each 6. ; 7. ; 8. if and 9. ; 10. ; 11. end if 12. if 13. ; 14. end if 15. end for 16. end for |

The ECQA has a performance guarantee , which indicates we can obtain a solution is times of optimal solution in NP-hard problem [17]. The closer of value of to 1, the more approximation to optimal solution. In this paper, the ECQA can achieve a lower bound ratio of when the cardinality as of set is not less than three, i.e. . Next, we will prove the following theorem about the performance guarantee of ECQA.

**Theorem 2.** The ECQA can achieve a worst performance guarantee offor *.*

(15)

, where is the set in an optimal solution.

**Proof:** Let’s redefine as a vehicle added into in i-th iteration, Let denote , and . To prove inequality (15), the following two inequalities we can derive from [18], After iterations, we can get:

, (16)

(17)

, where denotes the sensing reward to . The detailed proof of inequalities (16),(17)can be found in [17],[18]. We can easily to know that (17) is equivalent to following inequality,

(18)

, where is selected at round but not added to due to overflow budget constraint . Applying (16) to (18), we get

(19)

, where the set means that an element belongs to set but not in set .

Assuming is greater than , if this were the case, is bound to be selected before and included in , so this assumption is invalid. Therefore, we can get,

. (20)

From (19), (20) the following inequality can be hold

(21)

, where is a natural base whose value is less than three, hence

(21)

, if and only if , the inequality (21) makes sense. Clearly, , and then

(22)

Owing to the final output of ECQA as good as if not better, this prove the performance guarantee of .

**EVALUATION**

Extensive simulations has been conducted to evaluation the performance of our proposed algorithm. The traffic trace dataset we used, the simulation setup, the compared algorithms, and the performance comparison and discussion are presented as follows.

**A. Real Traffic Trace Used and Simulation Setup**

In our simulation, to make the evaluation results convincing, the T-Drive trajectory dataset [19], [20] that contains a one-week trajectory of 10,357 buses. The total number of points in this dataset is about 15 million and the total distance of the trajectories reaches 9 million kilometers. We have imported the processed data into the Google Global Mapper, as figure 3 shows, the distribution of the trajectories of vehicles basically covers the whole traffic network of Beijing. Our simulation are performed on traces extracted from the dataset on February 3, 2008, 6 AM to 10 PM. Two sets of simulations are performed. In the first set, we randomly extract a small number of vehicles from processed dataset to participate in crowd-sensing, i.e., 30, so that the optimal solution can be found though an enumeration algorithm. In the second set, the number of vehicles is very large result in the enumeration algorithm is infeasible in polynomial time. Each vehicle is associated with a SR, and the SR of a vehicle is uniformly distributed in [0.7, 1.2].

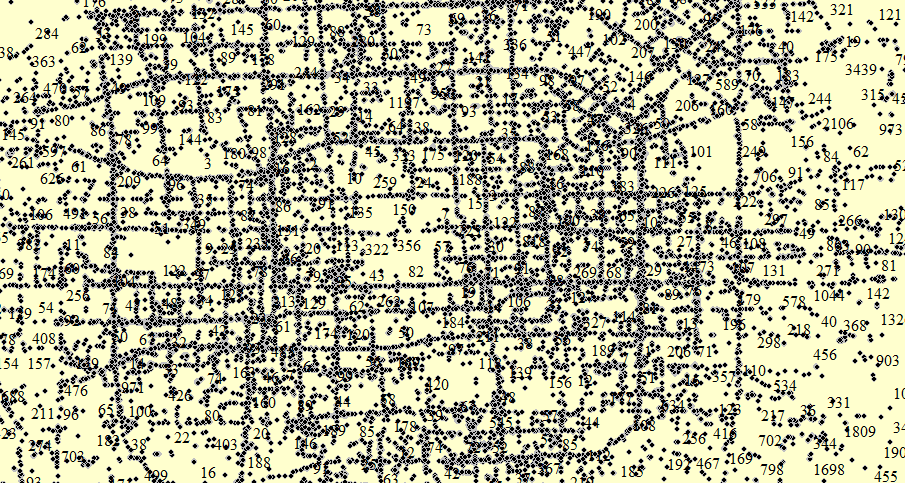
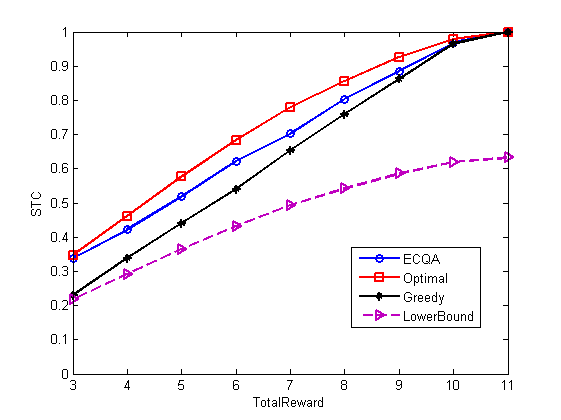


Figure 3. The distribution of the trajectories of vehicles in the dataset. In this figure, the number is the ID of each vehicles, the points is the current location of a vehicle at a specific time.

**B. Algorithm in Comparison**

The quality of crowd-sensing is related to STC, we evaluation how the budget constraint , the number of time period , and the number of candidate vehicles impact on the performance.In this paper, we compare the performance of our algorithm with two baseline algorithm. **1)** The enumerative algorithm (EA) can always get the optimal vehicles from the candidate vehicles by exhaustive search, however, the SVP is NP-hard, when the number of candidate vehicles is larger, it becomes infeasible to obtain the optimal solution in polynomial time. Thus, the EA is applied simply when the number of vehicles is small. **2)** The simulated annealing algorithm (SAA) is often used to solve optimization problems, we improve a SAA to compute the SVP for maximizing the STC. Furthermore, the results are also compared with the lower bound that is performance guarantee the optimal STC



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