

Parallelized Traffic Simulation in C++

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Abstract—This semester research project investigates the potential speedups and scalability of running a traffic simulation in parallel using C++ and OpenMP. These speedups are evaluated by comparing the sequential performance to the parallel performance when varying thread counts for a fixed-size, randomized input. While a large percentage of the program is inherently sequential due to computation, the process of transitioning from one state to another was parallelized.

Index Terms—OpenMP, Cellular Automata, Parallel Simulation, C++

I. INTRODUCTION

Extensive research and improvements have been made over the years in the field of study that is parallel computing. Falling within this domain of study is the topic of distributed simulation. As models become more and more complex, the execution time associated with these simulations becomes far too substantial for a sequential approach. A common remedy to this issue is to redesign the simulation to run in parallel. This research aims to see the benefits of running a parallelized discrete event simulation, and more specifically, a parallelized traffic simulation, over a sequential simulation. [1]

The ability to optimize light scheduling and move cars from one point to another in an efficient, organized manner is paramount for day-to-day travel. Being able to apply parallel computing to simulate increasingly large traffic environments leads to many interesting research topics and advances in road safety, traffic capacity, economic impact, among many others. The topic of simulating traffic flow for increasingly large sizes of roads is the topic of interest explored in this simulation. Real life traffic flow allows for movement when possible at all times, and by utilizing parallel computing paradigms and tools, the speedup of a traffic simulation should prove beneficial in seeing

how a particular road and intersection scales for an increasingly large number of cars funneling in and out.

Traffic simulation naturally lends itself to parallel computing paradigms. Decomposing the movement of cars into a sub-domain of problems and updating traffic flow in parallel from one state to another, just as normal traffic would run, is one method to improved performance. Thus, a parallel solution to traffic flow needs to be able to parallelize any movement and update that could be happening concurrently. The dynamic nature of traffic also plays a large role in this type of simulation but was handled to leave a larger emphasis on the updating of car movements. The following research being presented simulates traffic flow through a four-way stop, which includes two-lane roads from all directions. The traffic simulation was built with C++ utilizing a cellular automaton approach. The parallelization was made with OpenMP, an application programming interface (API) that supports shared memory multiprocessing. The following is an overview of the remainder of the paper: Background research on the applied tools and ideas used and reasons for why they were chosen, the sequential algorithm design and solution, the parallelization and results, and finally a summary with conclusions of the research.

II. BACKGROUND AND RELATED RESEARCH

Chances are if you have ridden in a vehicle, you have come across a four-way stop being controlled by traffic lights. A four-way traffic stop has roads leading from all four directions (North, South, East, West) where each direction takes a turn moving towards its destination as directed by the controlling traffic light. The traffic light operates in three states: red, green, and yellow. Green means go, red means stop, and yellow means slow down. Assuming each direction is at least a two-lane

road, and ignoring the possibility for a one-way street, any car driving on the outer most lane is capable of taking a right turn at the traffic light intersection if oncoming traffic is clear, regardless of the state of the light. Cars in the innermost lanes are also capable of making a left turn, given that their light is currently green. The light itself cycles on a timer allowing for each lane to have its own turn to proceed, which creates the flow of traffic. This four-way model is what our simulation is derived from, which will be explained in a later section.

The placement of cars along any road is relatable to a data model studied in computer science and related fields known as *cellular automata*. Formally, cellular automata are defined as a collection of cells on a grid that evolves during a number of discrete time steps according to a set of rules based on the states of neighboring cells. The rules are then applied iteratively for as many time steps as desired [2]. Cellular automata have been studied since the early 1950s and was initially used as a model for biological systems. The lattice structure and discrete state like approach of cellular automata was taken and applied to our simulation to represent individual, discrete states of traffic flow and positions of cars within a street. Another principle of cellular automata is localized interactions with nearby cells. Each car within this system must recognize the state of the cell that lies a step ahead in the direction it wishes to move in order to determine its next state. The different discrete representations of the states and interactions of the cars, the lights, traffic, and lanes in general will be explained later within the paper.

The general structure of the system has been described, now let's look at the tools and technologies used to implement the simulation. The entirety of this research project was developed in C++ 17. C++ is a statically-typed, compiled, middle-level, general purpose programming language developed by Bjarne Stroustrup in 1979. C++ was used to implement all of the simulation logic and sequential transitions. To parallelize this program, we used OpenMP. OpenMP is an Application Program Interface (API) that provides a portable and scalable shared memory model for parallel applications. OpenMP is designed for shared memory parallel programming. This was essential for our project. What drove us to choose OpenMP over MPI (Message Passing Interface), which doesn't have a concept of shared memory, was the potential costs of communication if the simulation were to be

run with an input size of 200,000,000. This would require an MPI implementation to have the processes broadcast the global automata system for every discrete state, which could be incredibly costly at scale. With OpenMP, this global system can be shared memory and operated on by all the threads, without the overhead of frequent, massive scale communication instructions for all processes to get back on the same page. Another common parallelization library is POSIX threads (or pthreads). We chose OpenMP over pthreads due to critical section concerns and keeping the threads in sync while accessing the shared data simultaneously. Pthreads offered too fine-grained control for the needed operations our system performs, and the flexibility given was overkill for this simulation's purpose. OpenMP is more high level than pthreads, and allowed for easier, more accurate division of tasks among processes. As a result, OpenMP was the parallelization tool of choice for this project. [3]

Now that the technologies and techniques have been selected to maximize our simulation specifications, a resource is needed for the execution, testing, and analysis of our program. In order to run high intensity simulations, for both thread count and input size, we would submit our project for execution as a batch job onto the Stampede2 computing cluster. Stampede2 is the flagship supercomputer at the Texas Advanced Computing Center, and consists of 1,736 nodes, and each has 48 cores and 192GB of RAM. This enabled us to run simulations with threads varying from one up to 64 threads on input sizes ranging from 200 to 200,000,000. [4]

With all resources in hand, we can discuss the history of traffic models. Parallelized traffic simulations have been implemented before and have evolved from relatively simple systems to very complex models. Here are some of the implementations that inspired the following research, and set the path for modern, parallel traffic simulations. One of the very first cellular automaton-based simulations was designed by Nagel and Schreckenberg. This simulation was developed for single lane traffic and was initially sequential. It utilized Monte-Carlo methods to describe start-stop waves as traffic grows more and more dense. While relatively simple, this model was used for traffic forecasts and analysis for years. As systems began to adapt multiple lanes of traffic and simulations were adapted to model high-density, urban areas, the need for parallelization quickly became realized. One of

the first thoughts for parallelization was decomposing the automaton into sub-systems. The issue with this approach was something we also discovered from testing, was that the communication overhead when the system scales becomes far too costly for efficient execution. Another approach that researchers sought out was dividing the system into preexisting time segments and eventually synchronizing the time slices. This also was not effective, as the outcomes of these time slices cannot be predetermined, as there must be an essence of randomness to keep the simulation true. Modern traffic parallelization utilizes methods for accurate systematic predictions to decompose the system into micro-states and optimize the computation to set-up the next state of the system while load-balancing the system splits to prevent massive communication costs. [5]

Where this research project attempts to differentiate itself is by simplifying some of the logic of the random states and primarily focus on the parallelization of the state transition without decomposition. The hope is that at a large enough scale, our state transitions of even massive systems will be able to see performance improvements through OpenMP parallelization. To do this, we have essentially simplified the next state logic for our four-lane simulation to adhere to a transition function of simply shifting each of the lanes towards the next determined state (computed prior to shift time). The next section of this paper will discuss the sequential implementation of the traffic simulation, how the states are determined, and the operation to transition from one discrete state to another.

III. SERIALIZATION TECHNIQUE

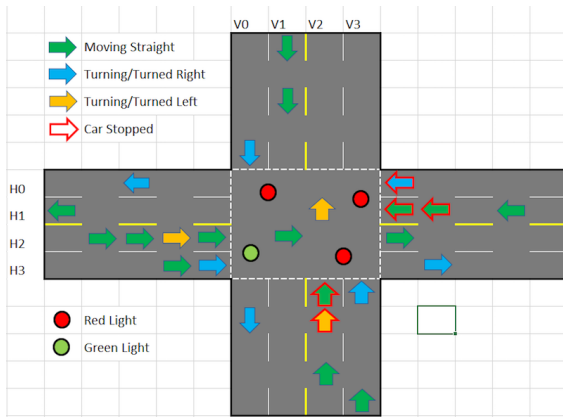


Fig. 1 Overview of simulation

To design our serial solution to the four-way traffic simulation, we began by deciding on using an array type data structure to represent each lane and store car states. Since our simulation runs with four horizontal lanes handling cars moving east and west, and four vertical lanes handling cars moving north and south, our solution uses eight arrays in total to hold all data. An array data structure was chosen for a few reasons. The first being because C++ arrays store memory contiguously, meaning the data is laid out next to each other with no gaps in between. This type of memory layout is ideal because it makes data parallelization simple, as well as allows for use of the cellular automata model. Data layout was the main reason that moved the design away from an object-oriented approach. Storing objects in C++ leads to offsets between data in memory, making it much harder to parallelize when the time comes. Within each of the eight arrays (roads) holds a variable number of cars represented by an integer value from 0, 1, 2, or 3 that each correspond to a specific action within the simulation. Each integer is defined as follows:

- 0: Empty
- 1: Car moving straight
- 2: Car taking a right
- 3: Car taking a left

The eight roads included in the traffic simulation also leads to a 4×4 intersection point holding 16 cells. This intersection point represents the cars that are moving to the other side of the road. To keep track of these cars we split the work between horizontal and vertical, where either of the horizontal and vertical arrays can be holding cars within the intersection at any state.

The last important aspect of designing the simulation was how to handle light timing for every direction. To have our light timing continuously looping a rotating array was used that shifted a single value to the right on a timer, which moved the state of one light on to the next. This way the light timing would continuously run until the simulations end.

Two different approaches were used as input to populate our roads for simulation. The first was input by csv, where the csv was filled with numbers representing cars and could be read in to populate road data.

| | | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|---|
| | | | 0 | 0 | 1 | 0 | | | | |
| | | | 2 | 3 | 0 | 1 | | | | |
| | | | 2 | 3 | 0 | 0 | | | | |
| | | | 1 | 3 | 1 | 0 | | | | |
| 0 | 1 | 0 | 0 | 0 | 0 | 0 | 2 | 2 | 0 | 0 |
| 0 | 0 | 0 | 0 | 0 | 0 | 0 | 3 | 3 | 1 | 1 |
| 3 | 3 | 0 | 0 | 0 | 0 | 0 | 1 | 0 | 0 | 0 |
| 1 | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 1 | 1 | 1 |
| | | | 0 | 0 | 3 | 1 | | | | |
| | | | 1 | 0 | 3 | 2 | | | | |
| | | | 1 | 0 | 1 | 0 | | | | |
| | | | 0 | 0 | 3 | 2 | | | | |

Fig. 2 Example input file

This input was useful when testing on smaller inputs and at the beginning of logic development, because it allows for controlled traffic states and expected output. The next type was randomized input. A command line argument is used to gather the dimensions of fo each road size and corresponding car types are randomly placed at every spot within each road based off of probability. This version of input allowed for increasingly large input sizes to be created and tested for more extensive testing once logic development was completed.

To confirm correctness of development, an important output function was also created. The main version of output, which cleanly represents a traffic simulation, was done using UTF-8 characters to represent lights and prints to the console showing an overhead view of traffic current traffic. At any time this output only represents the middle 20x20 view of the traffic, including the 4x4 intersection. This output leads to a minimum road size of 20 and allows for an easy view of the simulation regardless of the input size. To go along with this, important current road statistics are also shown to know when the simulation will be ending, such as car's exited, and how long each run of the simulation is taking.

The updating of car positions is where cellular automata comes in. Each car is moved to its next state in the simulation by shifting them to the next spot in the array. This array shifting is done by indexing, which will prove to be of interest and explained later on. Before proceeding, each car must check ahead of them in the direction they are moving for an empty cell, which is in line with the model of cellular automata. Throughout the simulation cars are continuously checking states before moving through each cell until the simulation is complete.

The simulation is run state by state until every car has exited. As the state simulation begins, each state is done one time followed by a short sleep time before the next states run. To run the simulation, there is a pre-set

sleep time that allows for state by state printing to the console between each step in the simulation, which can also be lowered to run a faster simulation. This set sleep time also controls the time each green light is set for, called light time, to scale it according to the speed and size of the simulation. Lastly there is a clear time, which serves as the simulations yellow light, and allows for cars within the intersection to clear out before the next light becomes green. Green and yellow lights are calculated in the following way:

$$\text{Light time} = \text{sleeptime} \cdot \text{factor}$$

$$\text{Clear time} = \text{sleeptime} \cdot 4$$

where *factor* is scaled to the size of the simulation. Clear time is always set to 4 because the intersection size is constant.

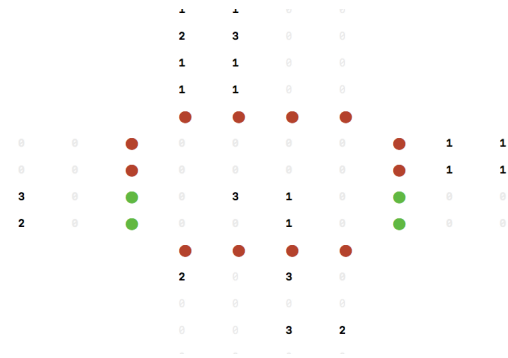


Fig. 3 State during green light

The above figure (Fig. 1) represents the simulation during a green light, where cars moving to the east are allowed to move forward. Cars in other lanes must wait unless they are turning red, which you see behind each red light.

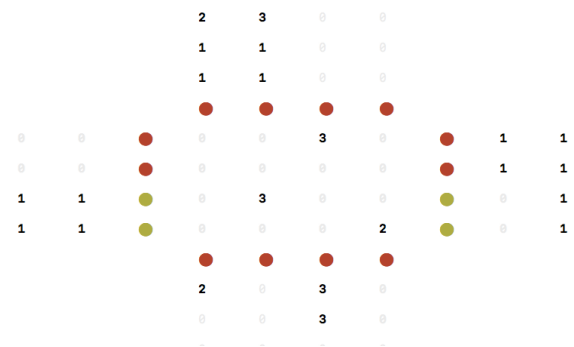


Fig. 4 State during yellow light

The next figure (Fig. 2) represents the simulation during a state of clearing the intersection, or the yellow light state. During this time period any cars within the intersection are moved forward to clear the road for the next light, which will be shown in the following image.

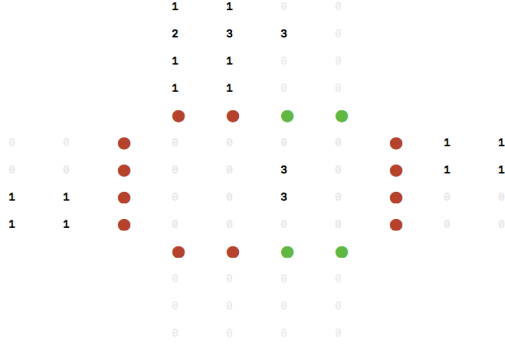


Fig. 5 State during light change

Once a yellow light is finished, the next light is set to green and those cars are allowed to move. Fig. 3 shows the next light turning green once the previous light states are finished.

During green light states of the simulation, every car in the appropriate lane is moved up in the array. Each movement is done by looping over the array and setting indices to be $\text{array}[i] = \text{array}[i+1]$. Any car that is labeled a 1 will not have to check for cars in front of them during a green light, since cars ahead of them are also consistently moving. For car's labeled as 2's, they are moved into the corresponding new lane from horizontal to vertical or vertical to horizontal, because it is changing directions. This is done by checking if a 2 labeled car is also in the correct corner spot in the intersection. Lastly, 3's during green lights are treated similarly to right turning cars, except they move in a different direction and at a different spot within the intersection. This process is done until the light state is switched to the next green light.

During yellow light states of the simulation, behavior runs the same as during a yellow light until every car is out of the intersection point. During this time cars are halted to get ready for the next green light run of the simulation. This part of the simulation constantly runs for 4 states, because that is the maximum time needed to clear out the intersection. Once the intersection is cleared the light moves to the next in line to begin the process again.

Green light states of the simulation also has more going on than just the movement of the cars in its own

lane. During any given green light, the ends of roads and cars coming up to lights are also being updated. So while cars are moving forward, other cars in every other lane are also either moving out of the simulation (cars past the light) or moving up to the light intersection to wait for their time to move forward. Furthermore, any car waiting at a red light, while another green light is active, is allowed to move forward if it is a right turning car and the intersection is clear enough. Right turning cars on green lights check ahead of them, as well as one spot to the left, to be sure it will be safe turning right. Otherwise, it stays put until it is allowed or the light changes. The updating and movement on other roads while one road is green is what makes the simulation truly act as real traffic.

As cars come to the end of roads (front or end of arrays) a total count of cars is being updated. Once this count of cars hits 0, the simulation has finished. The clearing of cars leaving the simulation, as well as those coming up to lights, is called during every state, making it the most cost heavy part of the solution, and the section most open for parallelization.

IV. PARALLELIZATION TECHNIQUE

During the serial design of the traffic simulation we kept parallelization in our mind. One of the best benefits of OpenMP is the ability to develop a sequential solution to a problem and work inside out of the design to make it parallel, which is the exact approach we took. There is one computation that our entire traffic simulation depends on to run: array shifting.

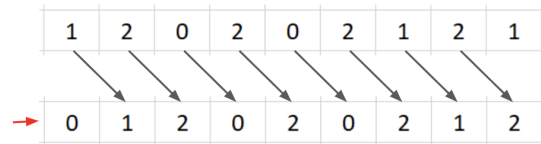


Fig. 6 Example of shifting an array.

The shifting of arrays to move cars state to state is the bulk of the simulation and the problem we could boil down our parallel technique to. Before we integrated any parallel design into our solution, we created smaller subset problems as a proof of concept.

Before being able to test the shifting of arrays in parallel, we had to fix one major issue that occurs during the parallelization of this type of problem: loop carried dependency. The shifting of arrays depends on the ability of changing state by looking ahead. In a parallel design of array shifting, the process of shifting each position in

the array would be divided among p processes, which results in a problem.

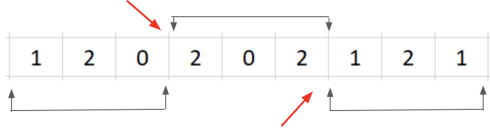


Fig. 7 Loop carried dependency

Suppose there is an array of size 9 split up among 3 processes as seen in Fig. 7. The red arrows point out the spots where the dependency occurs, because each process needs data that another process is handling to complete its job correctly. The shifting of arrays within a loop carries this dependency because a statement in one iteration of the loop depends on a statement in a different iteration of the loop. This means that the parallelization of shifting an array cannot be done simply by giving each process a size of the array to perform the shift on.

To solve this loop dependency issue we made use of next state arrays. The next state array is simply an array that holds the same value of the array to be shifted so that each process has access to the data it needs without it being changed anywhere else. The concept of a next state array successfully solves the loop dependency issue, but also adds extra overhead in continuously updating and storing such arrays for every state in the simulation, which will be touched on later.

After solving this issue we ran subproblems of our simulation by testing the shifting of an array of size 20,000,000 using a varying number of threads in OpenMP vs. Shifting sequentially. The timing results of these tests are shown in Fig. 8.

| Threads | N = 20,000,000 | Serial |
|---------|----------------|---------------|
| 1 | 0.0433568 sec | 0.0355666 sec |
| 2 | 0.0232553 sec | 0.0327267 sec |
| 4 | 0.0122165 sec | 0.0335324 sec |
| 8 | 0.00633528 sec | 0.0335273 sec |
| 16 | 0.0039911 sec | 0.0342329 sec |
| 32 | 0.00400028 sec | 0.0338233 sec |
| 64 | 0.00494359 sec | 0.0337914 sec |

Fig. 8 Parallel vs Sequential array shift

The number of threads performing the shift we varied from 1 to 64. The results show that a performance benefit started to occur immediately with the addition of a second thread. As the number of threads increased the

performance also steadily grew compared to the results of the sequential shift. With these results we were able to confirm the parallelization technique we would be using and begin integrating into our actual simulation.

Due to the logic heavy nature of the sequential solution, we had to decide on the most beneficial areas to parallel while keeping the integrity of the simulation. During any green light state in the simulation, the most work being done is happening on the outside, with cars driving away from the intersection or up to the intersection, while the cars in the green light lane are moving forward. The updating of all other cars requires the most work throughout each simulation state. This made us decide to parallelize all movement of cars happening outside of those moving because of the green light. By doing this, we make it so movement of cars in each lane is occurring in parallel, which is true for real traffic flow. So as cars move through the green light lanes, cars moving away and out of each road are being updated in parallel. To parallelize this aspect of the solution we parallelized the for loops responsible for updating each of the necessary areas of the road. OpenMP makes this process very simple to do, and because our project was extremely loop heavy, it makes it all the more viable of a tool.

After integrating our parallel solution into our sequential project, we tested our simulation with a varying number of threads and problem sizes using stampede, similar to our subproblem tests. We used input sizes ranging from 20 to 200,000 and varied the number of threads from 1 to 64. The results we got back are shown in Fig. 9.

| Size | Threads (t) | | | | | | |
|------------|-------------|--------|----------|----------|----------|----------|----------|
| | t = 1 | t = 2 | t = 4 | t = 8 | t = 16 | t = 32 | t = 64 |
| 20 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 | 0.00 |
| 200 | 0.01 | 0.01 | 0.06 | 0.10 | 0.31 | 4.20 | 7.50 |
| 2000 | 10.00 | 0.35 | 0.35 | 2.00 | 4.40 | 13.00 | 41.00 |
| 20000 | 1.10 | 12.00 | 17.00 | 29.00 | 68.00 | 190.00 | 470.00 |
| 200000 | 290.00 | 870.00 | 1,000.00 | 1,300.00 | 1,800.00 | 3,600.00 | 9,000.00 |
| Time (sec) | | | | | | | |

Fig. 9 Parallel Simulation vs Sequential

V. SUMMARY OF RESULTS

Quisque ullamcorper placerat ipsum. Cras nibh. Morbi vel justo vitae lacus tincidunt ultrices. Lorem ipsum dolor sit amet, consectetur adipiscing elit. In hac habitasse platea dictumst. Integer tempus convallis augue. Etiam facilisis. Nunc elementum fermentum wisi. Aenean placerat. Ut imperdiet, enim sed gravida sollicitudin, felis odio placerat quam, ac pulvinar elit purus eget enim. Nunc vitae tortor. Proin tempus nibh sit amet nisl. Vivamus quis tortor vitae risus porta vehicula.

VI. CONCLUSIONS, LESSONS LEARNED, AND FUTURE WORK

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