

Web Processing - Standardised GIS Analyses for Cable Route Planning

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add as final part

CCS Concepts: • Computer systems organization → Embedded systems; Redundancy; Robotics; • Networks → Network reliability.

Additional Key Words and Phrases: datasets, neural networks, gaze detection, text tagging

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1 INTRODUCTION

Sometimes, finding the shortest path is not sufficient. Additional parameters also have to be taken into consideration. As the steepness of a road or the soil, play an important role for the building cost of a road or pipeline [11]. For planning the additional routes for a power grid, additional aspects as legal regulations and acceptance by the local population have to be taken in consideration. Also technical aspects, as the effects on the grid stability might be further points to consider.[10]

Due to the increasing need for renewable energy wind off shore wind turbines are source which currently supplies 5.5 % annual percentage in 2020 of the German energy mix. [4] For wind energy in general highest efficiency can only be achieved with high wind speeds. Highest wind speeds are reached along the cost lines in the north of Germany. In contrast, most consumers, as industry are situated in south Germany. Source and consumer have to be linked via new power lines.

Other methods as the multi-criteria decision analysis take further aspects and stakeholder as experts, public and decision maker and into consideration.[8]

For planning a possible route for a power line the least cost path algorithm is applied. The least cost path algorithm is a Dijkstra algorithm applied on a raster map. The vertices of the graph are the centers on neighboring pixels in all possible eight directions. The weights of the edges are the local costs to travel from one pixel to the neighboring pixel. The costs might be physical costs, as the local slope, but also can be composed on other factors as the acceptance rate for the land usage of a given class. The least cost path algorithm consists of at least two sequential steps. 1) The first step is to aggregate the costs of traveling from the starting point to a given set of end points. This step generates the aggregated cost

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raster of the total cost that are needed to travel to a point, from the cost raster. 2) In the next step the back tracking, the route of the actual least cost path is calculated. For each ending point the path via the lowest cost neighbor is taken until arriving at the starting point.

The aggregation is implemented in a priority queue. Hence a point with a lower cost is evaluated earlier as a starting position to evaluate the cost of its neighbors, than a point with higher costs. The aggregation is implemented with early stopping. After the last end point has been reached an aggregated cost the aggregation stops and the back tracking starts.

2 METHODS

We retrieve a set of different spatial data-sets from public sources as a basis to create the cost raster. Field of study are the counties of Cuxhaven and Osterholz in the state of Lower Saxony, Germany. Areas protected by different European and National conservation laws are provided by the German Environment Agency as Web Feature Service (wfs) [1].

The nationwide land coverage (ATKIS) with a scale of 1:250000 are provided by the Federal Agency for Cartography and Geodesy [3]. The nationwide power grid (tags: 'power': line) has been retrieved via OpenStreetMap [9]. Local data as houses at Level of Detail 1 are offered by the State Office for Geoinformation and Land Surveying of Lower Saxony[7]. In addition, local planning geodata for the land usage are taken from 'Metropolplaner' (Planning data Lower Saxony & Bremen)[6]

PyWPS[2] is used to offer the least cost path algorithm as a Web Processing Service (wps). The initial implementation of the least cost path algorithm is based on the implementation for the QGIS-Plugin 'Least Cost Path'[5] in version 1.0.

The different layers from the different entities are optionally filtered, buffered and then rasterized. Filtering the layers of the files for special attributes enables to further differentiate. For example makes it possible to differentiate between heath and uncultivated land. Adding a buffer can be used either to convert a line objects as power grids and streets into a polygon with the correct physical width, or to add minimum distance from an existing planned area to the new power grid. Each of these rasterized layers are given a weight, or cost that expresses the cost of using land covered by this layer. The costs of all layers are aggregated with the maximum function. Thus, an area covered by multiple layers is uniformly used with the highest costs. For every area in the study area, that is not covered by any layer, is given the default cost. The costs have been grouped into different levels (see table 1) starting from preferential areas with very low costs, via no restrictions, which is the default, used when no other layers are covering the local area, to restricted, strongly restricted and prohibited areas with high costs. These higher costs resemble the degree how much a local area should be avoided, while routing the path. The ratio of the higher costs to the lower costs directly translates into the additional diversion in pixels the algorithm is willing to go, for

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avoiding an area of high costs. Thus, as prohibited areas describe a legal obligation, not to use these areas or only to the utmost minimum, the weight that resembles the costs for these types of areas, has to be especially high.

The rasterization transforms a vector into a raster. The rasterization can be executed in two different ways. In both ways, the rasterization can be imaged, as the old vector is layered over the new raster grid with the new given resolution and the new affine transformation and the coordinate reference system of the vector. Both rasterization techniques differ in how the pixels are selected, that describe, that a geo-object overlays the pixel. The pixels can either be described as overlaid with a geo-object, when either the center of that pixel is overlaid by the geo-object, or any part of the pixel is overlaid. Hence, the version with any part overlaid is called all touched True. The version where a overlaid pixel center is required is thus called all touched False. All touched False is considered the default (see figure 1).

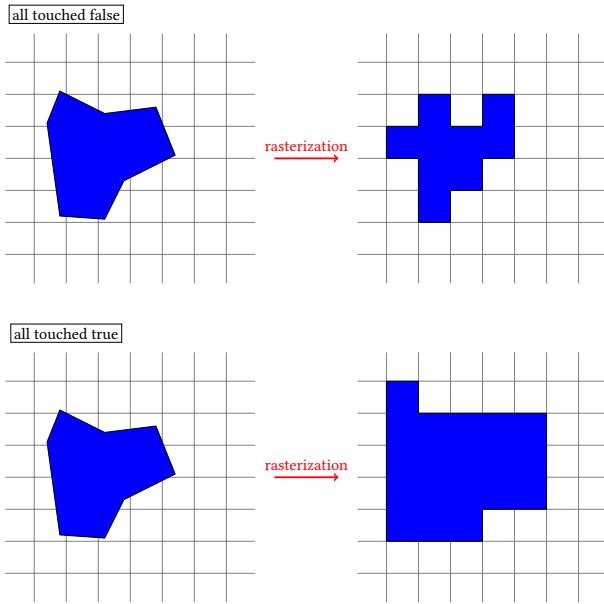
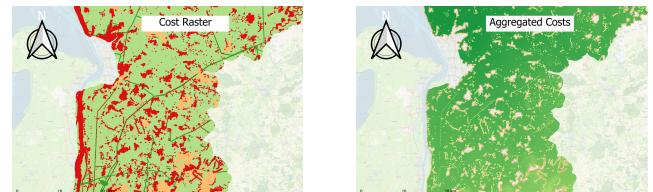


Fig. 1. Graphical example for rasterizing a vector (left blue), to a raster (right blue) with either all-touched False (above) or all-touched True (below).

Table 1. Used levels of costs, the applied numerical equivalent and example layer this cost have been used for.

Cost Level	Cost	Example
Prohibited	500	Conversation areas as National Parks, Buildings
strongly Restricted	10	Conversation areas as Bird Reserve
Restricted	5	Protected Landscape Area, Industrial Areas, motorway, railway
No Restriction	0.5	Default
Preferential	0.1	Power Grid, Motorway and Railway Buffers



(a) Cost Raster.



(b) Aggregated Cost Raster.



(c) Least Cost Path.

Fig. 2. Figures of Cost raster and the resulting aggregated Costs and the least cost path for a resolution of 50 m.

The completed list of layers and the processing applied to them, can be found in **Supplement S1**.

The whole stack of the cost raster, via the aggregated costs to the resulting least cost path can be shown with an example for a starting cost raster of 50 m resolution and a rasterization with all touched False (see 2). Because of the early stopping strategy used in the aggregation sub-paths with high costs have not been fully computed. Instead, the execution stops early after reaching the end point. Because the end point ends at a power transformer, which is a building type, the paths end at in a Prohibited Area. Therefore, areas even farther away from the starting point have been explored first.

3 RESULTS

In this chapter we want to show the different cost raster, that were created from the very same set of layers, but computed for different resolutions. From this different raster the cost paths are calculated and compared. In the last step the raster with lower resolution were used to calculate in a way, that they shall result in similar paths as if the paths were computed from a high resolution raster.

3.1 Cost Raster

The cost raster contains all the costs as weights for the geographic region of the study area. The regions outside the study area are given, a no-data value and will not be used for the calculation of the least cost path. It is decided to use the maximum value, for any place in the raster, that is covered by several rules at the same time. When the resolution that is used for the rasterization is smaller than the object size, than the effect of the rasterization with all touched True or False is limited. For all touched True any part of the pixel that is covered by the object, will attribute that whole pixel to the object. Thus, the object appears to be halve a pixel size larger in all directions. As can be seen in figure 3 that shows a detailed view of the

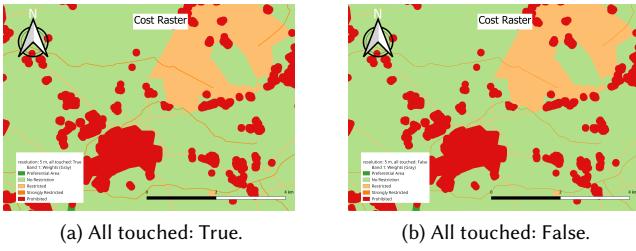


Fig. 3. Figures of the cost raster. Contrasting the for different values in all touched at a resolution of 5 m.

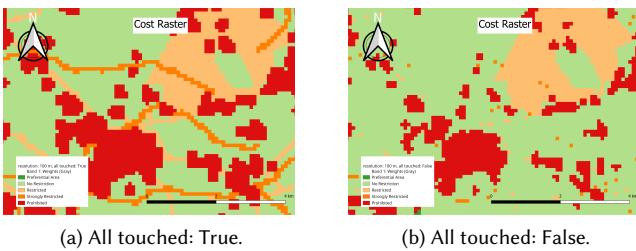


Fig. 4. Figures of the cost raster. Contrasting the for different values in all touched at a resolution of 100 m.

costs for village of Beverstedt. Due to the maximum aggregation of the costs, the average cost of the raster of all touched true will be over estimated. All touched false will be a better description of the real size of the object.

In contrast when the resolution the is much less, than the size of the object the described behavior changes. On one hand, while the area, of the pixel is increased for all touched True, also the area for which the cost is overestimated increases. On the other hand while the pixel size for all touched False increases, not only the over estimated area increases for that pixel as describes for all touched true, but in addition the object is less probable situated in the center of the pixel. The consequence of the pixel is, that will decreasing resolution that object is not included in the rasterization. Hence, hence for all touched false lower resolution leads of a loss of information. Because the default is relative small compared the over effect is a underestimation of the costs. The figure 4 shows for the resolution of 100 m, that while larger are still included in the map they appear to be much larger. On the contrary smaller objects might not be included. Objects that are small on in one dimension as streets will be included in a stochastic manner. Described by the likely of that a object of that sized overlaps with the pixel center. Thus, with having larger areas and more objects, with higher costs, all touched True rasterization might more likely lead to longer roots and more likely in blocking the direct spatial path.

3.2 Least Cost Paths

For each resolution the costs paths were estimated for the rasterization with setting all_touched False and all_touched True.

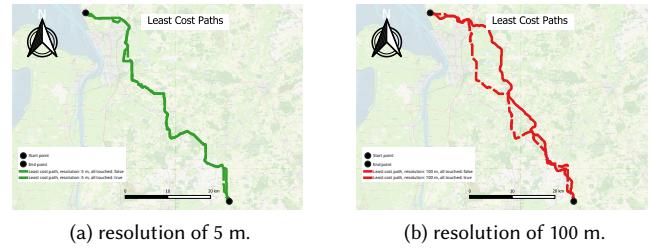


Fig. 5. Figures of the least cost paths. Contrasting the paths for different resolutions. Paths computed from all touched false raster are indicated by dashed lines. Results from all touched True are indicated by continuous lines. Higher resolutions are indicated by the color green, lower resolutions by the color red. Using OpenStreetMaps as base map.

The hypothetical path starts at a transformer about 6 km north the container terminal Bremerhaven and then end at a transformer in the south east of the Osterholz county.

The distance of both paths is calculated with the mean minimum distance. For every vertex P_i in the path L_1 the minimum between the vertex and the path L_2 is computed and afterwards the minimum distances are averaged (see equation 1).

$$d_{mean} = \frac{1}{|L_1|} \sum_{i=1}^n d_{min}(p_i, L_2) \mid p_i \in L_1 \quad (1)$$

This equation is used, to measure the extent of similarity between the paths.

$$d_{max} = max(\sum_{i=1}^n d_{min}(p_i, L_2)) \mid p_i \in L_1 \quad (2)$$

Hence, the mean minimum euclidean distance between the two paths can be used to compute the similarity. As different table 2 shows the distance between the two paths decreases with increasing resolution. In addition, this tendency is depicted in figure 5 for the calculated cost paths of 5 m and 100 m resolutions.

In contrast the largest distance between the paths (see equation 2) will be used, to estimate the minimum distance to the areas that still should be examined to guarantee a, that at least cost path found in this limited space is still likely to be optimal.

At the same time the differences in the aggregated costs stay constant. When normalize the aggregated costs by the resolution. Then on one hand it can be seen, that the all_touched False under estimate the costs and that this tendency scales linear with the resolution. On the other hand, the all_touched True least cost over estimates the aggregated costs on a linear scale of the resolution. Therefore, the difference for the normalized least cost paths is reduced on scale by the resolution.

Comparing the all_touched True rasterization and all_touched False for the same resolution in contrast with the paths of all_touched False rasterization at the different resolutions the later paths are more similar. The mean average distance between the 100 m resolution run and the 5 m resolution run is 257.97 m.

Interpretation

Table 2. Least cost paths as length for the different resolution (res) of the raster, including the mean minimum distance and the maximum minimum distance and the aggregated (agg.) costs. From the agg. costs the differences of the agg. costs and the corrected (corr) agg. by resolution are given.

res /m	$l_{al=f}/m$	$l_{al=t}/m$	d_{mean}/m	d_{max}/m	agg. cost _{al=f}	agg. cost _{al=t}	Δ costs	corr agg. costs _{al=f}	corr agg. costs _{al=t}
5	76136.27	78002.00	126.04	1065.00	18665.923	19616.756	-850.00	93329.60	97584.77
10	75430.10	77936.57	277.92	1590.00	8931.245	9731.175	-799.95	89312.45	97311.75
25	75422.85	78422.85	313.75	1621.15	3354.869	3872.656	-517.78	83871.73	96816.40
50	76135.02	70619.95	1140.01	4950.00	1409.023	2300.073	-891.05	70451.15	115003.65
100	76283.80	74120.73	1946.41	6016.64	640.516	1572.268	-931.70	64051.60	167226.80

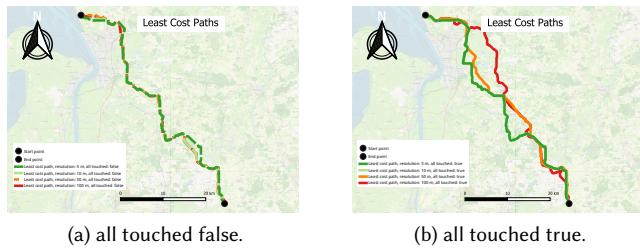


Fig. 6. Figures of the least cost paths. Contrasting the changes of the least cost paths for the different results, depending on the parameter all_touched. Paths computed from all touched False raster are indicated by dashed lines. Results from all touched True are indicated by continuous lines. Higher resolutions are indicated by the color green, lower resolutions by the color red. Using OpenStreetMaps as base map.

The similarity of all all_touched False runs is higher than, the similar between the all_touched False and all_touched True runs with the same resolution, except for the highest resolution.

Hence, in an overall perspective paths of the all_touched False runs stay in a similar region, while paths of the all_touched True coverage strongly to the paths all_touched False runs. This behaviour is depicted in figure 6. On a more detailed level, it can be seen, that also the Paths of all_touched converges the all_touched True path. But the extent is smaller. The length of the the paths only differs to a maximum of about 10 %. The least path distance for higher resolutions can be lower, because new paths, between regions that are forbidden in higher resolution can open. On the other side the length of the paths can increase, because with higher resolution more vertices will be used.

The zonal stat (see table 3) for a buffer of 100 m (5 m) around the path has been used, to estimate the percentage of which costs levels are around the path. When using all_touched True rasterization with higher resolution the tendency is to use a higher percentage of the Preferential Level and less the NoRestriction Level. The ratio of the 100 m buffered least cost path, strongly shifted to Levels lower costs.

There is no strong tendency for the all_touched False least cost paths.

3.3 Execution time

In theory, the execution time should increase with the square of the resolution, because higher resolutions result in a higher number of pixels and thus data points the aggregated costs needs to

be calculated for. A full logarithmic fit for several repetitions of the execution shows, that the execution time scales with power of 2.1997 ± 0.007 of the inverse resolution. With the caveat of a low number of samples this can equally be success fully be fitted to a second degree polynomial of the inverse resolution with a r^2 for the test set of 0.99 and a the squared inverse of the resolution with a r^2 for the test set of 0.99. Hence, the order of magnitude

The total execution time consists of two parts. The aggregation of the costs and the back tracking of the least cost to find the path.

3.4 Faster Processing of the Cost Path Algorithm

The final least costs paths should between the least cost paths of the lower resolution, with a tendency to be nearer to the paths resulted by the all touched false rasterization. The first step is to optimize the calculation speed is, only to calculate the least cost paths for this smaller area. Another method, is to improve the prediction of the medium resolution itself and thus reduce the need for a computation in higher resolution.

3.4.1 Compare least cost paths, for overlay of both rasterizations.
As all touched true rasterization overestimates and all touched true underestimates the real costs. A weighted mean will describe the real costs more precise. As present work indicates, that the weight should favor the all touched false raster. The best weight should be the percentage of the pixel, which is covered by the object, but this can not be computed in this work. Thus, the best weight has to be searched. An alternative might be to compute the cost raster in higher resolution, but than to reproject the to a smaller resolution with a using a (linear) interpolation of the of the weights.

While the aggregated thus can be speed up. The time needed for the back tracking stays unchanged.

The optimal ratio of overlaying all touched false and all touched true cost raster for 10 m resolution is estimated via the resulting least cost path. The mean distance of least cost paths for different ratio has been estimated to the path from the all touched false raster of the next higher (5 m) resolution. Table 4 shows, that distance decreases with the higher ratio from 1:1, 2:1, 4:1 and than increases with higher ratio 8:1, 16:1 and so on. In addition, the distances to the original paths from the all touched false and all touched true raster change with the applied ratio of the overlayed raster. So that, a lower ratio increases the similarity to the path of the all touched true raster, the similarity to the paths from the all touched false raster increases with the ratio.

3.4.2 Compare least cost paths, for down sampled cost paths. As an alternative to the super position of the all touched true and false

Table 3. ratio (r) of Category percentages of each least cost path for a buff of 100 m (5 m) around the least cost path.

res /m	all touched	rPreferential%	rNoRestriction%	rRestricted%	rstronglyRestricted%	rProhibited%
5	False	4.7 (5.4)	58.7 (58.9)	8.8 (8.4)	0.7 (0.7)	27.1 (26.7)
10	False	19.6 (33.5)	68.5 (64.5)	1.0 (0.8)	0.8 (0.3)	10.1 (0.9)
25	False	19.2 (34.2)	68.9 (64.9)	1.0 (0.2)	0.7 (0.1)	9.7 (0.6)
50	False	20.4 (33.2)	68.0 (66.2)	0.9 (0.1)	0.7 (0.0)	10.1 (0.5)
100	False	21.1 (30.7)	69.1 (68.8)	1.1 (0.0)	0.7 (0.0)	7.9 (0.4)
5	True	18.9 (28.5)	67.3 (66.4)	1.3 (1.6)	1.0 (0.5)	11.5 (3.0)
10	True	18.9 (33.7)	66.6 (63.4)	1.6 (1.4)	1.4 (0.6)	11.5 (1.0)
25	True	18.7 (31.9)	65.5 (65.5)	2.0 (1.3)	2.5 (0.7)	11.4 (0.6)
50	True	9.1 (13.0)	75.7 (83.0)	3.9 (2.0)	4.2 (1.6)	7.1 (0.4)
100	True	7.0 (10.1)	73.8 (81.9)	5.5 (3.9)	8.5 (3.6)	5.2 (0.4)

Table 4. Length of the path computed from the overlaying of all touched false and true raster and the mean distance of the paths to the paths calculated from the all touched false 5 m resolution and all touched false and true raster of 10 m resolution.

r	d _{5 al=f} /m	d _{10 al=f} /m	d _{10 al=t} /m
1:1	119.6	285.50	47.21
2:1	97.11	263.51	74.19
4:1	40.13	206.38	100.16
8:1	41.73	169.02	137.34
16:1	56.69	153.32	152.71
32:1	56.69	145.56	162.09
64:1	163.48	10.61	272.36

raster for the same resolution, the all touched false raster was down sampled to 10 m, 25 m, 50 m and 100 m with bi-linear interpolation. With this method smaller structures still can be seen in the cost raster, although the resolution is reduced. The distances of the paths that are computed from the bi-linear down sampled 5 m resolution raster (all touched false) is from table 5 shows, that a low distance to path of the 5 m resolution raster was only obtained when down sampling to a resolution not to low. Only when down sampling to a resolution of 10 m, is the computed path considerable close to the path from the higher resolution raster. It holds true, but to a much reduced extend to the path computed from the raster, that was down sampled to a resolution of 25 m. The opposite is true for the lower resolution raster which is more similar to paths computed from the all touched true cost raster. For every path from a down sampled raster is more similar to a path computed from an all touched true raster, than an all touched false raster, although the all touched false raster of the 5 m resolution was used for down sampling.

3.4.3 Restrict search to a buffered around the least cost paths. Construct a polygon form the two lines. Buffer the polygon with twice the max minimum path distance.

This enabled the possibility to run a 2.5 m resolution cost raster and clip it to the extent of the polygon. This clipped 2.5 m raster for all touched true did only slightly change the path. While the all touched False raster, leads to a totally new segment at the end of the path. Due to the small resolution, that a small path with the

Table 5. Length of the path computed from the bi-linear down sampled raster and the mean distance of the paths from the down sampled raster to the paths calculated from the all touched true and all touched false raster of the same resolution as the down sampled raster.

res /m	1 /m	d _{5 m} /m	d _{al=f} /m	d _{al=t} /m
10	75980.62	59.34	219.35	143.63
25	70205.27	385.79	558.12	432.77
50	69217.86	730.82	693.42	255.70
100	66667.87	1681.3	1605.63	400.55

extent of about 2.5 m width became passable. This small path is a power line next to road between which build a cone in a protected landscape area. The street and the protected landscape area are both restricted areas, while the power line is preferential. This showing, that the way the cost raster is created in the first place can play a vital role, in the end result. So that a nuance, can cause a detour. When this behavior occurs, the polygon can not guarantee to include the least cost path. Therefore this polygon should be overlaid with a polygon around the shortest path.

3.4.4 Check solution for least cost path between different points.

4 DISCUSSION

As shown, the need for computation time increases with the power of two with the resolution. Similarly, the usage of main memory increases. Which in turn limits the processable data points and resolution. On the error only scales linear with the resolution. Hence, there is a diminishing return of smaller errors, compared to compute time and resources used.

Therefore, this work tries a) to reduce the needed compute power and b) decrease the deviation for a given resolution.

For b), two methods have been used to increase the similarity of the paths computed from medium resolution raster, to the path of the highest resolution raster. These methods can be used as surrogates for the more complex calculation of the least cost path with the higher resolution. In the first method a bi-linear down sampling of the higher resolution raster has been applied and in the second method, the all touched false and true raster where averaged in different ratios, to computed the optimum mixed raster, for the used costs. While the second method of using an averaged raster,

a higher similarity to the path from highest resolution raster, the down sampling method is more simple and does not need to be optimized for the given costs. Hence, it is easier and widely applicable.

For a), to reduce the computational complexity, the calculation of the medium resolution raster has been applied, to reduce the search space of the aggregation. While this method reduces the calculation time and usage of main memory, the backtracking part stays unchanged.

As the original least cost path QGIS plug-in the used algorithm stops the least aggregation of the costs after the final end point has been found. This early stopping might result in sub-optimal paths around the end points for some edge cases, where the connection via another neighbor might be more optimal.

The set of rules that are used create the cost raster, includes a rule for creating a buffer around buildings which is set to the level **prohibited** areas. While the used data set for buildings, also includes power poles, the area of the level **preferential** power grid, includes isles of high costs. In further works, these should be excluded.

In this work, the effect of computation costs and deviation of the results, is examined for a very limited set of points. Also, only the costs of finding the least cost path from one starting point, to a single end point has been considered. When, multiple endpoints are used, the computation cost for the aggregated cost raster has only to be computed once. On the other hand the effect early stopping is not as dramatic, because the algorithm would only stop early for the last end point with the highest cost. When calculating several paths from one raster, the benefits of chapter 3.4 is reduced. Especially, the pre-calculation on lower resolution raster and buffering of the resulting paths as a restricted search area decreases in its effectiveness. As the number of paths rises, fewer of points in higher resolution cost raster will be deselected for the final estimation of the least cost path.

In this work, the single cost raster layers aggregated with the maximum function. Another possible aggregation function is the sum. Each aggregation function can be justified, by a different interpretation of the costs and its scale. The reasoning of selection the maximum function is, limiting the maximum costs. When the **prohibited** level is used as the highest level. Then higher levels are prohibited within the concept. This is an area even more prohibited, when it is included in two different rules of the level? On the other side, this aggregation is unable to differentiate between these nuances, as the sum function is. This way, one can differentiate between, different sub-levels. One consequence is, that a small mediation between high and low single cost raster, in the final cost raster is possible.

The fact, that all touched False raster lead to more similar results compared to high resolution raster, is due to the fact, that the default level is relatively low. In case the default level would rise, the effect probably would flip for low resolution raster. For high resolution raster, this effect would still hold true, because the fact, that the raster pixel center is used for sampling, reflects the original geometry better.

Interpretation: Interpretation the Cost Paths are much nearer smaller, than 100 m! No problem because buffering is included in the cost raster. Not algorithmic speed-ups as pre-compilation, JIT, vector units, multi-core

5 RELATED WORKS

6 CONCLUSION

When using the researched strategies, the on medium resolution raster, the computation for high resolution results might successfully be reduced, without compromising the run time for worse distances to the least cost path from the high resolution raster.

ACKNOWLEDGMENTS

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A RESEARCH METHODS

A.1 Part One

A.2 Part Two

B ONLINE RESOURCES

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