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Energy Efficient Route Planning Using VANET

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Energy Efficient Route Planning Using VANET

By

Nazmul Huq Sumon

A Thesis

Submitted to the Faculty of Graduate Studies
through the School of Computer Science
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at the University of Windsor

Windsor, Ontario, Canada

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ABSTRACT

One of the key challenges in conducting dynamic route planning is the process of collecting and disseminating instantaneous travel data in real time. Recent studies are evaluating VANET (Vehicular Ad Hoc Network) and its associated WAVE (Wireless Access in Vehicular Environment) standards to facilitate this process. In these studies, travel data accumulated from vehicle OBUs (on board unit) are shared with other vehicles over DSRC (dedicated short- range communication) medium using centralized or distributed approach. In most studies, data collection and dissemination process are not scalable enough for high density traffic environment. Specifically, with a centralized approach, if traffic management center (TMC) or Road Side Unit (RSU) performs route planning for vehicles, there will be many bidirectional communications between the centralized entity and vehicles, leading to higher channel congestion in heavy traffic areas. With a distributed approach, information shared by other vehicles might not be useful or pertinent for some vehicles, leading to wastage of channel bandwidth. Methods used for data collection also need to be intelligent to count in nontraditional circumstances to achieve accuracy. In this thesis, we have proposed a three tiered architecture for data collection, analysis and dissemination. In addition, 1) we demonstrated the concept of queuing delay at intersection for travel time calculation and developed a hybrid metric that considers average travel time and occupancy rate, 2) we offload the computation of route planning to vehicle OBUs and 3) we developed an algorithm that determines the area of propagation for data that needs to be disseminated. We evaluated the performance of our approach progressively using VEINS, SUMO and OMNET++ simulators.

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To my wife Sharmina, without your unconditional support, I couldn't have come this far. I highly value your patience, encouragement and kindness and I owe you a lot for that.

DEDICATION

Dedicated to my beloved parents and sister for their support and sacrifice.

TABLE OF CONTENTS

DECLARATION OF ORIGINALITY	III
ABSTRACT	IV
ACKNOWLEDGEMENTS	V
DEDICATION	VI
LIST OF FIGURES	IX
LIST OF TABLES	X
1. Introduction	1
1.1 ITS and VANET:.....	1
1.2 Motivation:.....	2
1.3 Problem statement:	3
1.4 Solution outline:.....	5
1.5 Thesis organization:	7
2. Background	8
2.1 Terminology	8
2.2 Dynamic Route Planning	11
2.2.1 Tools used for performance evaluation.....	12
2.3 Literature review on route planning based on VANET:	17
3. Proposed Fuel Efficient Route Planning	20
3.1 Traffic Management Center (TMC) Functionality	23
3.1.1 Create Edge to RSU association	23
3.1.2 Maintain Current Traffic Information	26
3.2 Vehicle OBU Functionality	30
3.2.1 Send Travel Time Updates	30
3.2.2 Update Vehicle Route	30
3.3 RSU Functionality	34
4. Experiment Setup and Results	36
4.1 Experiment Setup.....	36
4.1.1 '.net' file generation.....	37

4.1.2 Graph node and edge extraction	37
4.1.3 Internal junction and edge elimination	38
4.1.4 Node, edge and RSU association, and driving permissibility	38
4.1.5 RSU placement selection	38
4.1.6 Database setup	39
4.1.7 TMC setup	40
4.1.8 Vehicle setup.....	41
4.1.9 Vehicle – RSU interaction.....	42
4.1.10 Route file / Demand generation	42
4.2 Results.....	43
5. Conclusion	47
5.1 Future Work.....	47
References.....	49
Vita Auctoris.....	53

LIST OF FIGURES

Figure 2.1 DSRC/WAVE protocol stack 1.....	9
Figure 2.2 Control (CCH) and Service (SCH) Channels of DSRC Spectrum	10
Figure 2.3 A map in .osm format as viewed in SUMO	13
Figure 2.4 Simulation capture showing internal junctions and edges, and signalized intersection	14
Figure 2.5 a very high level overview of connections between SUMO, VEINS and OMNET++	16
Figure 3.1 High level overview of proposed approach 1	21
Figure 3.2 Edge-RSU relationship using $n=2$. The colored RSUs will broadcast metric value of prospective edge 'e' with start node 'j' for nearby vehicles to influence route planning	24
Figure 3.3 TMC process flow chart	29
Figure 3.4 Vehicle application flowchart	31
Figure 3.5 Driving permissibility is required to be consulted for correct operation of FERP	33
Figure 3.6 RSU application process flowchart	35
Figure 4.1 High level setup of the experiment 2.....	41
Figure 4.2 Screen capture of the simulation run from OMNET++ 1	44

LIST OF TABLES

Table 3.1 Terminologies used for proposed approach 1	22
Table 4.1 Notations used in experiment 1.....	36
Table 4.2 Tables used in the database1.....	40
Table 4.3 Summary of simulation properties1	43
Table 4.4 Result of setup 1.....	44
Table 4.5 Result of setup 2 1.....	45
Table 4.6 Performance comparison with no dynamic route planning and no queueing delay	46

1. Introduction

1.1 ITS and VANET:

Intelligent Transportation System (ITS) - was first envisioned in the early 1980's primarily for surface transportation with the purpose of improving safety, efficiency and convenience [1]. ITS was first officially recognized by Transportation Equity Act (TEA-21), passed by the US Congress in 1988 [2]. Three main disciplines of ITS are Advanced Traveler Information System (ATIS), Advanced Vehicle Control and Safety System (AVCSS) and Advanced Transportation Management System (ATMS) [2]. While the ATMS discipline addresses monitoring and management of real-time traffic, detections of traffic pattern, driver error, system performance and vehicle state are addressed by AVCSS. ATIS provides notifications on incidents, road conditions, restrictions, weather etc. through variable message signs in roads and highways.

With the advent of Controller Area Network (CAN) bus [3] that are installed in vehicles 1996 and newer, a wide array of vehicle's system state and performance data can be tracked and recorded such as velocity, acceleration, different engine state, wheel state, brake state etc. Additional state data can also be gathered using Radio Detection And Ranging (RADAR), Light Detection And Ranging (LIDAR), and other sensor devices [31]. Vehicular Ad Hoc Networking (VANET) [1] brings in new dimension to ITS since these state data can be disseminated and shared among cars using On Board Units (OBU) that are installed in vehicles and, or infrastructure services like Road Side Units (RSU) for analytics that can facilitate all three disciplines of ITS.

VANET got a large boost in its development when US allocated dedicated short range communication (DSRC) channel for vehicular operation in 1999 [2]. VANET got more formal specification with DSRC's 802.11p amendment to the traditional 802.11 standard along with other standard extensions of 1609.x in WAVE [1][2]. Apart from VANET's safety application to assist with collision avoidance and accident data dissemination, numerous research is being conducted to develop applications that can aid Traffic Information/Management Centers (TIC/TMC) to address efficient route management, route planning and diversions [21].

1.2 Motivation:

One of the key contributing factors of global warming is traffic congestion due to overloaded and inefficiently planned road infrastructure and traffic management system. Apart from pollution, congestion costs an estimated \$160 billion of lost productivity in the USA alone [4]. Canadian cities are not behind [5] and by 2050 an estimated 9 billion people with 2.9 billion cars will share the road [6][7]. More vehicles require more well-planned traffic management system along with a balanced and efficient infrastructure expansion plan. ITS comprising of a set of emerging technologies for surface transportation can be an effective tool to assist policymakers in building such a plan. VANET - now an integral part of ITS, is capable of sharing pertinent information of road and vehicular data with other vehicles and Road-Side Units in 'real time'. These disseminated data then can be analyzed by the central traffic monitoring system to coordinate route planning and scheduling of vehicles. This will result in reduced congestion on roads and provide faster, fuel efficient trip time for vehicles. However, it is important to also consider network usage and scalability factor as they directly impact efficiency of such setup.

1.3 Problem statement:

At present, route planning using traditional Global Positioning System (GPS) [8] advises drivers on the shortest trip based on static route database and with the help of subscribed data feed over 'Radio Data System' that broadcasts current traffic congestion over 'Traffic Message Channel' [9] and more recently using push notifications over the internet [11]. The inefficiencies of such route planning are mainly as follows -

- Does not consider the results of aggregated load on alternative lighter paths where the vehicles are rerouted to [10]
- Due to low bit rate of traffic message channel [9], delay in broadcasting such information is considerably high leading to route planning using outdated information
- Use of internet service requires data subscription
- The timing is important since the current congestion doesn't mean it will remain congested for an indefinite period. If infrequent or, occasional congested routes that gets cleared in short time are considered during initial route plan, vehicles will be subscribed into frequently congested route leading to further poor traffic distribution.

One way to tackle the problem of outdated data is to have instantaneous road data for each road segment that can be analyzed in centralized or distributed manner. The parameterized road segments represented as graph edges can also be recalibrated for dynamic weight redistribution to meet the demand of traffic monitoring center if necessary. The instantaneous road data can

be collected using a combination of roadside units, and OBUs installed in the vehicles. Vehicles then can be rerouted based on some decision-making process and on the basis of gathered road data that are usually converted into metrics. The decision making can be conducted either by the ego vehicle alone or, by a cluster of adjacent vehicles that are in certain close proximity to each other or, by a centralized traffic monitoring center or, by any combination of them [12][13][15][20].

A commonly used road data for calculating edge weight is the average trip time of vehicles collected as they pass through edges [12][13][15][17][19]. However, proper considerations need to be taken on - how trip time data are collected, where those data are assessed and how the assessed data are disseminated. These considerations are important to achieve maximum route planning efficiency with minimum channel congestion and bandwidth stress on the network. For example consider the following cases –

- If route planning is performed by the traffic monitoring center, there will be numerous one to one communication between the vehicles and the traffic monitoring center which is not scalable.
- If the route planning is performed by ego vehicles, analyzed data from traffic monitoring center needs to be disseminated in proper areas that are applicable to ego vehicle.
- If trip completion time for edges is used as the method for calculating travel time, vehicles 'stuck on an edge due to prolonged congestion at approaching intersection or onward

edges' provides delayed feedback of that edge resulting erroneous reporting of that edge to be congestion free.

1.4 Solution outline:

In this paper, we closely followed the work of Hamed et al. [12] in collecting real-time trip data where travel time are collected instantaneously on edges and used immediately for road metric calculation. In addition, we proposed three modified approaches in collecting travel time data, calculating edge metrics and disseminating the data as follows -

A. Offload route planning computation to OBUs:

We offload the tasks of performing 'travel time calculations of individual edges' and 'route planning' to the vehicles themselves instead of RSUs or traffic monitoring centers. In other words, OBUs are responsible for receiving travel time for all vehicles, process and send them to TMC. TMC, in turn, send updated Current Trip Time (CTT) to RSU for broadcast. Vehicles do not query RSU/TMC for route planning, rather they do the planning by themselves using updated CTTs.

B. Develop an RSU-EDGE relationship:

This method is for choosing how far the congestion data of a particular edge should be disseminated, so a vehicle can determine whether that edge should be selected in its route plan or, not. This is achieved by binding of an RSU R , with an edge set E , where R is responsible for broadcasting metrics for E . By using this three-tiered structure, we limit the size of distant edge-metrics-data packets an ego vehicle receives and thus put less stress on

the network. The decision of choosing the boundary of such dissemination is empirical since having too short boundary means vehicles might choose locally optimum path and face heavily congested areas down the route plan that are not known to them in advance. Having the boundary too broad can also be a problem as sparsely and occasionally congested distant areas that quickly become uncongested might alter initial route plan of vehicles to choose lower degree of congested areas that are persistently congested.

C. Consider intersection queue or red light delay in computing edge metrics:

If there is a long queue at an intersection due to traffic backlog on next edge and/or, traffic light phasing, vehicle(s) may not be able to deliver travel time updates to RSUs. This is the case when vehicle broadcasts the travel time for the previous edge, upon getting into a new edge. This results in RSUs erroneously assuming that the edge is free of congestion. An alternative approach is that vehicle waiting in the queue sending travel time that equals to the time to reach current position plus delay time that is beyond certain threshold.

In this thesis, we have used SUMO [22] as road traffic generator and OMNET++ [23] with VEINS [24] for DSRC's WAVE stack simulation. Using the simulations, we evaluated the performance of our approach compared to the methods used previously by other researchers. Several simulations are run using different value of queuing delay and RSU-EDGE relationship as described above. The results indicate that the proposed approach will lead to better aggregated fuel efficiency and shorter trip time for vehicles.

1.5 Thesis organization:

The rest of the paper is organized as follows. Chapter 2 discusses related terminology and literature review relevant to this area. Chapter 3 demonstrates our proposed approach, setup, and algorithms. Chapter 4 provides the result analysis. In chapter 5 we conclude and summarized our work with possible future research in this area.

2. Background

In this chapter we review some basic terminology and fundamental concepts to ITS and VANET. We also describe in-depth the current techniques for dynamic route planning available in the literature that are most relevant to this thesis.

2.1 Terminology

WAVE (Wireless Access in Vehicular Environment) refers to collective standards of 802.11p - an extension of traditional 802.11 for operation in high speed vehicular environment with low latency and 1609.x – that defines the additional OSI equivalent layers necessary to support such communication using DSRC (Dedicated Short Range Communication) [25]. In most papers WAVE protocol and DSRC protocol are used to refer same set of standard interchangeably.

DSRC refers to the ‘dedicated 75 MHz spectrum in the 5.9 GHz band allocated by US Federal Communications Commission for automotive use’ and the corresponding set of protocols and standards to support the communication using that spectrum [25]. The primary motivation of DSRC was to facilitate the development of collision avoidance application [32]. The application will rely on data from vehicle states such as speed, acceleration, position, brake states etc. and data from road side infrastructure. Road side infrastructure often termed as RSUs can act as communication relay point for distant vehicles and can also act as an intermediary between vehicles and traffic management center. Using a set of message syntax defined by SAE’s (Society

for Automotive Engineer) J2735 standard, vehicle state data are encapsulated with WSM (WAVE Short Message) for dissemination. For data dissemination purpose, all equipment such as OBUs and RSUs needs to be of DSRC standards to maintain interoperability of such communication.

Figure 2.1 depicts the WAVE protocol stack in general. DSRC equipped devices need to maintain communication with two channels instead of one as in traditional LAN based communication. Therefore, DSRC incorporates an additional MAC sublayer for channel coordination and switching as defined by the 1609.4 standard.

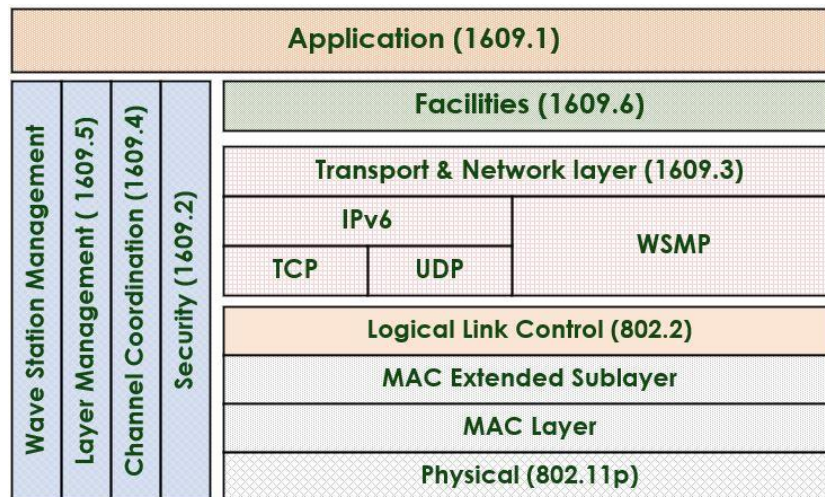


Figure 2.1 DSRC/WAVE protocol stack

CCH and **SCH** refers to control and service channels of the DSRC spectrum. Out of the 75 MHz spectrum 5MHz is used for guard band and rest is divided into 7 channels – each with 10 MHz spectrum. The control channel is used for carrying management and higher priority messages using WSMP while the service channel are used for other types of data using TCP/UDP. Security of payload using either WSMP or TCP/UPD is provided by WAVE’s 1609.2 standard suit as

depicted in figure 2.2. Channels 174, 176 can be combined to form one 20 MHz channel – 175. Similarly channels 180 and 182 can be combined to form a 20 MHz channel – 181.

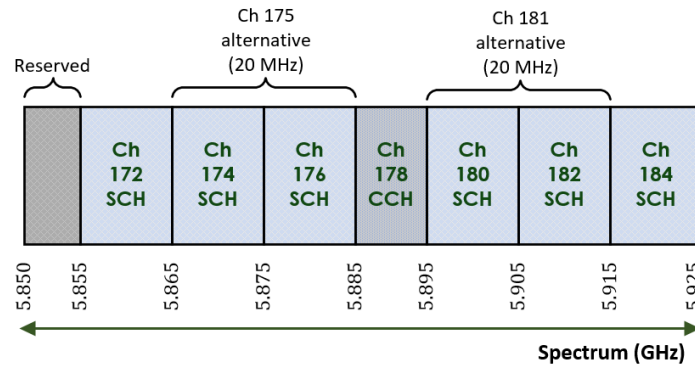


Figure 2.2 Control (CCH) and Service (SCH) Channels of DSRC Spectrum

WSM refers to WAVE Short Message that uses either control or service channel of DSRC to carry time-sensitive, high-priority information using WAVE Short Message Protocol [25]. WSM contains extension like channel number, data rate, and transmit power so the upper layer can indicate the purpose the message usage [33]. The syntax of such time sensitive messages is defined using SAEJ2735 standard. Basic Safety Message (BSM) is an example which is delivered using WSMP with a WSM header extension. BSM has two sets of information where set 1 is mandatory for initial deployment of DSRC in USA and set 2 is optional. Set 1 of BSM is the information set that contains space and time critical states of vehicles for the development of safety applications [33].

CAN BUS is a computer network, interconnecting embedded systems that control the vehicle and vehicle’s performance. CAN in general refers to the protocol of using such bus where the protocol works by exchanging messages between the components independently without the use of a host computer for coordination.

2.2 Dynamic Route Planning

Route planning in general involves the process of selecting a set of roads connecting source and destination with some constraints involved such as fastest, shortest or most fuel efficient route to destination. Each of these constraint imposes different ways of selecting one or more metrics based on which the route planning algorithm decides the best route. The typical metric stored in route planning instrument such as a GPS is **travel time**. Dividing a given road segment's length by posted speed of that segment produces travel time of the respective segment. While travel time provides the fastest route to destination, an even simpler metric – **travel distance** which is the actual length of road segments - can provide shortest route to destination. Routing planning that considers **travel cost** makes fuel efficient route calculation that can include additional metric such as road slope, length of idle time during transit etc. [27]. Route planning can also consider **easiness of driving** as described in [34] that factors in driver's preference for number of signals, number of turns and road width of the planned route. Advanced route planning may also consider statistical traffic patterns possibly involving historical data analysis along with current probe data to estimate future travel time [28][29].

Route planning using GPS make use of preloaded map data for route determination. The validity of some data such as road closure, new road development etc. are dependent upon how recently the map was loaded into the GPS unit. GPS can also receive some basic road state information over RDS-TMC (Radio Data System – Traffic Message Channel) [34]. Due to limited channel bandwidth [9], data received over RDS-TMC cannot be used to make real time route planning decision.

Route planning using VANET involves the process of probing current road and vehicle state data and disseminating the probed data for use of other vehicles using distributed and, or centralized approach. In distributed approach vehicles share data with adjacent vehicles with the formation of a cluster [13] and in centralized approach data is directly sent over to a centralized entity for further processing [17]. The data probed, can be sourced from vehicle's CAN bus, GPS, passenger's electronic devices and other available sensors such as camera, radar, LIDAR etc. while the centralized entity can be road side units and, or traffic monitoring center. VANET also brings new possibilities in route determination such as cooperative route planning [REFs] that distributes traffic to reduce congestion but also factors in driver's historical and current preference such as avoidance of toll routes, highways etc. [36][37].

Performance evaluation of route planning methods in most cases involves the use of simulated environment as setting up practical testbed for a large scale research is expensive and unfeasible [26]. For VANET based route planning, a network simulator that implements the VANET infrastructure for communication along with a road traffic generator is necessary.

2.2.1 Tools used for performance evaluation

Open Street Map is an open source editable world map database that gets build upon community contribution of volunteered geographic information. The maps are downloadable for free in .osm format which is also an acceptable map format for road traffic generator SUMO.



Figure 2.3 a map in .osm format as viewed in SUMO

SUMO is a road traffic generator that is microscopic and multimodal - meaning different transport such as vehicles, pedestrians and public transport are modeled explicitly [22]. SUMO build its road map by using node and edge definition files named '*.node.xml' and '*.edge.xml'. Alternatively, it can also import open street map format and covert it to '.net' file which represents the map. Edge definition includes shape, lane, speed, length and traffic type of respective edges where node definition includes intersection type, coordinates and included lanes for respective nodes. Traffic generation is done through the definition of '*.route' file. For demand generation, route file can be constructed using 'Activity-based demand generation', random trips, O/D matrices defined by the traffic assignment zones etc. [22].

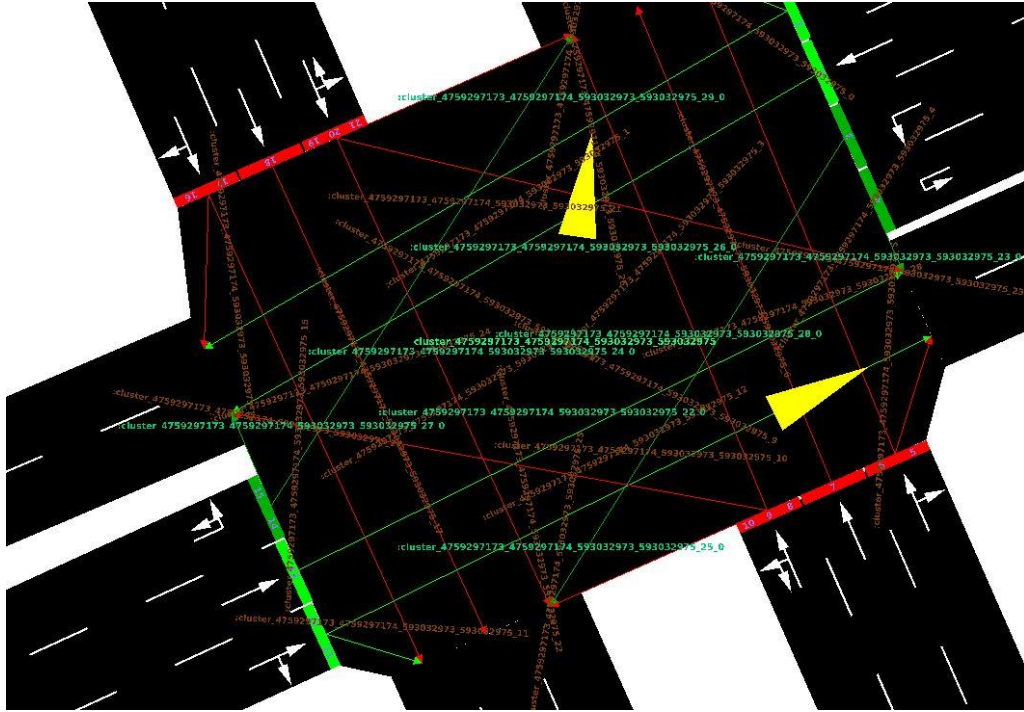


Figure 2.4 Simulation capture showing internal junctions and edges, and signalized intersection

TraCI refers to SUMO's online interaction server that provides interface to query, regulate or control traffic parameters or characteristics during simulation.

TMC – throughout this paper, is referred to as Traffic Monitoring Center that processes 'data sent by vehicles and RSUs', analyze those data, store the analyzed data for future use and purge obsolete data as necessary.

Junction refers to regular road's intersection in SUMO with predefined or imported traffic priority behavior from map. Traffic priority defines which traffic has the right of way through the use of stop sign and, or signalized intersection.

Internal Junctions and Internal Edges create links between lanes of two different road segments inside a junction. During graph construction and query regular Junctions are treated as nodes and regular Roads are treated as edges.

Traffic light phasing refers to the duration of different states such as green, amber and red for traffic lights in an intersection.

Network Simulator in general simulates protocol specific communication between nodes (or, hosts). The protocol definition and behavior of such communication are programmed into the simulators. A user of the simulator has the ability to choose a protocol and to define parameters of the communication and node's characteristics using the simulator's API, descriptor or configuration files. **OMNET++** is a network simulator that is modular and component based and is extensible to suit most network protocols [23]. OMNET++ enables user to model existing network protocols or user defined custom protocols that are used in communication network. Modules that controls the behavior of the protocols, are programmed with C++. Interaction between modules and their behaviors are set by the user using '*.ini' (initialization) and '*.ned' (network descriptor) files.

VEINS – a framework written in C++ - translates SUMO's road traffic vehicles into network nodes in OMNET++ and provides the mobility factor to them in adherence to WAVE's working mechanism. It provides the base for vehicular network simulation that closely implements 'WAVE architecture and different models like physical layer, channel switching, interference, propagation, antenna pattern, obstacle shadowing etc.' to make the simulation very close to real world [24]. At the physical layer, it extends OMNET's implementation of 802.11 to 802.11p to

support VANET. In addition it implements Path Loss Model and Obstacle Shadowing Model to bring real world radio propagation scenario. Models are also defined for channel sensing, radio switching, and transmission window. A specific 1609.4 module is defined to support Enhanced distributed Channel Access, (EDCA) which is responsible for frame queuing and transmission based on priority.

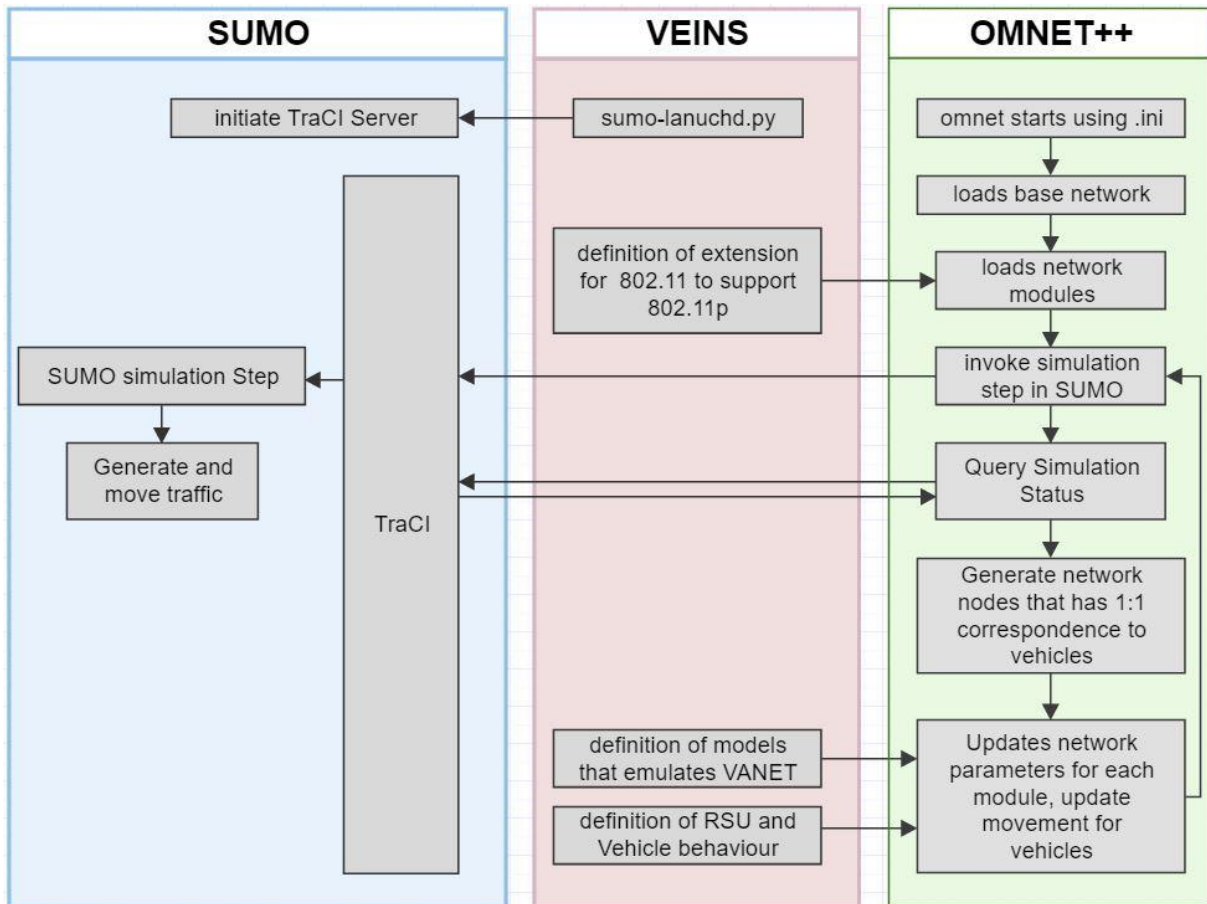


Figure 2.5 a very high level overview of connections between SUMO, VEINS and OMNET++

VEINS also provides bi-directionally coupled simulation by which control of vehicle in respect to its changing network environments and based on user specified demand can be reflected back to the road traffic simulator. This way road traffic and network simulation framework can work

together giving a notion of single simulation behavior [26]. Figure 2.5 depicts a very high level overview of connectivity between SUMO, VEINS and OMNET++.

2.3 Literature review on route planning based on VANET:

In [13], Joshi et al. used clustering algorithm for vehicles for collecting real time congestion information using GPS and for propagating the collected information using epidemic diffusion - also known as rumor model [14]. The system was developed around the principle that only vehicles - 'deviating from posted speed limit combined with the prior knowledge of frequent congestion history of a given road segment' - needs to communicate the information. The downside of this decentralized approach is 'occasional congestion that are sparsely formed' may not be communicated to the distant traffic in sufficient time for alternate route planning.

In [15], Keshavarzi et al. proposed a system that amalgamates information on congestion from sensors installed on the road and from inter vehicle communication through rumor. A cost function that considers dynamic metric on segments along with expiry, delay and uncertainty was proposed. The main limitation of this approach is how much congestion information on what roads are to be exchanged between 'road side units and vehicles' and between the vehicles was not clear. If congestion information on every roads of a locality or city are to be exchanged, the packet size for transferring such data would be considerably high resulting in bandwidth stress [16].

In [17], Collins et al. proposed a traffic management system that collects traffic data directly from vehicles, process the data and using 'generalized Floyd shortest path algorithm',

suggests best routes to the vehicles based on their current positions and destinations. The problem with this system is the centralized single tier approach where vehicles are directly reporting to a central server and the central server directly proposing routes to vehicles. Apart from scalability issue, this approach would put significant of stress in network bandwidth because of the noisy communication overhead unless other approaches to mitigate the channel congestion is used [18].

In [12], Noori et al. the authors proposed a method where RSUs on each end of roads calculates passing vehicle's travel time, averages the travel time for certain number of vehicles and broadcast the data to other vehicles and traffic information center. To calculate the travel time for a road segment, a bidirectional communication scheme between the vehicles and RSU is established. First as a vehicle enters an edge which hosts an RSU, it receives a timestamp from RSU. The timestamp is carried by the vehicle and delivered to next RSU upon arriving on the end of the edge. RSU then calculates the travel time by subtracting the timestamp from the current time and share this with other RSUs. Vehicles query RSUs for route planning of their sources and destinations, RSUs in turn consults with traffic information center to provide such route planning back to vehicles. The communication scheme for this approach is also have the same problem of being quite chatty because of the bidirectional inquiries between vehicles and traffic information center for determination of route planning. Also vehicle OBUs are underutilized since they do not perform route planning and travel time calculation of their own as TMC and RSU do those processing on vehicles' behalf.

In [19], Change et al. proposed a hybrid approach that considers recent congestion data from google map and data gathered and shared between vehicles to estimate future travel time and make route planning decision. First, data from a proposed App installed in driver's smartphones are utilized in calculating travel time, average speed and fuel consumption. Next, the collected data are shared using VANET with vehicles within a certain distance and up to a certain time. Progressively, as more data are collected, more accurate picture of the road status of a surrounding area is realized for an ego vehicle. The ego vehicle then also collects information on congestion from Google Map and calculates final metrics for road of its surrounding area that gets feed into an A* algorithm for route plan. The limitation of this approach is, the shared data from a vehicle might be useless for a cluster of vehicles who will not use the roads of which the data was shared. In addition, in an area populated by heavy traffic, this scheme also can contribute to channel congestion due to the large amount of information shared between vehicles.

3. Proposed Fuel Efficient Route Planning

The purpose of our proposed approach is to be fuel efficient in terms of lower aggregated emission and lower aggregated trip time for all vehicles. The functionality of the proposed approach is implemented in 3 different components, as shown in Figure 3.1. Each component is responsible for carrying out its own functions and communicating with the other components to transmit/receive information as necessary. The main tasks implemented each component are discussed below.

1. TMC functionality: The TMC is responsible for traffic analysis based on the information relayed over from the RSUs. TMC performs calculation of road metric using average travel time, intersection delay factor and occupancy window. To determine the set of road segments an RSU is responsible for, 'Edge to RSU association' algorithm is used which stores the association dictionary in TMC's database for RSU's use. TMC also purges outdated information from the database to minimize query time for the RSUs.
2. Vehicle functionality: Each vehicle is responsible for calculating travel time for each road segment it has travelled, and broadcasting them. In addition route planning algorithm run (section 3.2.2) to calculate the desired route is carried out by the OBU of each vehicle independently.
3. RSU functionality: Each RSU is responsible for receiving travel time updates (ttu) from the vehicles and transfer the updates to TMC's database. The transmitted travel time are accumulated in TMC via transit RSUs. Each RSU then queries the

metrics of road segments that the respective RSU is responsible for and broadcasts them for vehicle use.

Fig 3.1 shows the high level interaction between three main components of our proposed approach. The map container on the right shows interactions between RSU and Vehicles and their message format for communication.

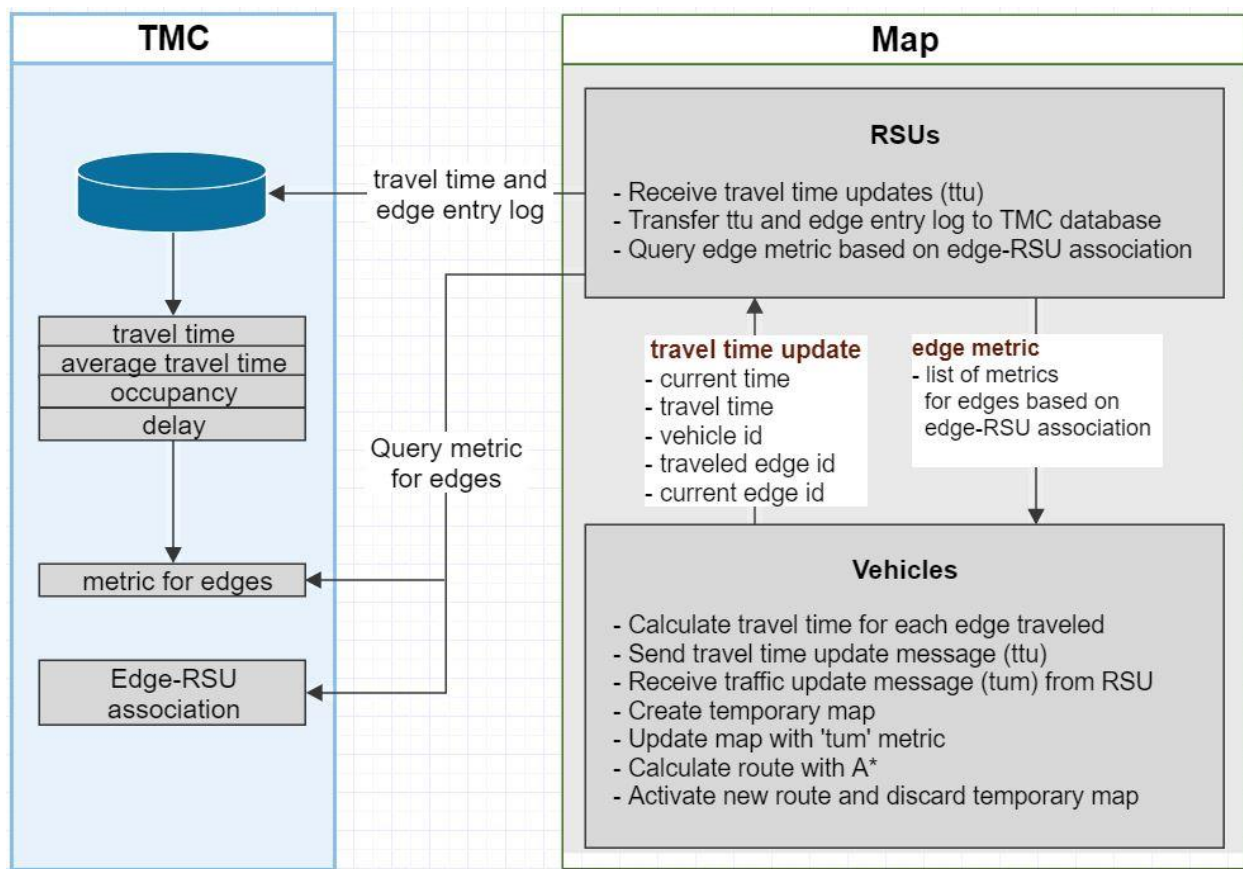


Figure 3.1 High level overview of proposed approach

In the following subsections we will discuss each of the above three components in detail. Table 3.1 introduces some of the terminology that will be used in the following sections.

Table 3.1 Terminologies used for proposed approach

Term used	Purpose
'BaseWaveAppLayer'	Refers to VEIN's parent class that emulates DSRC's WAVE protocol stack.
'edge_entry_log'	A table that holds timestamps of the entries of vehicles as they enters a given edge. Use for calculation of 'occupancy_rate'.
'first_timestamp' and 'last_timestamp'	Time stamp of the first and last entries queried by TMC's application that falls both within the 'max_update_entries' and 'max_update_interval'
'max_update_entries'	Maximum number of 'ttu' entries that are considered in 'ttu table' to calculate average travel time for an given edge
'max_update_interval'	The offset from current time step to a time step in past. The offset value indicates how recent the update entries should be considered.
'occupancy_rate'	Percentage of length of an edge that is occupied by vehicles during the 'occupancy_window' of that edge.
'occupancy_window'	A time window that spans the standard travel time for an edge in the past from the current time
'queuing_delay'	Number of seconds that a vehicle stuck in an intersection
'tmc_run_frequency'	Interval in seconds on which TMC application runs
'ttu table'	A table that holds all 'ttu' message entries from vehicles
'tum'	Traffic Update Message, sent by RSUs
'ttu'	Travel Time Update Message, sent by vehicles
'validity_bit'	A 'ttu' message with 'validity_bit' set to 1 indicates this message is originated from a vehicle that is stuck in an intersection for a time beyond configurable 'queuing_delay' threshold.

3.1 Traffic Management Center (TMC) Functionality

3.1.1 Create Edge to RSU association

In our proposed approach, RSUs do not perform route planning on behalf of the vehicles rather the vehicles themselves do so by receiving the edge cost information of a limited surrounding area of around the respective ego vehicle. It is thus important to cap the amount of edge cost information being broadcasted by a particular RSU, specifically the edge set of which the cost information is broadcasted must be relevant to the surrounding area of interest of the vehicle receiving the broadcast.

We therefore developed an algorithm that establishes relationship between an edge and a set of RSUs where the RSUs are responsible for broadcasting metrics for that particular edge. When determining an edge 'e' that will be associated to a set of RSUs 'R' - taken a given RSU 'r' 's junction as center point 'c' where 'c' 's outgoing edge is 'e', we are interested for adjacent junctions that are 'n' hops away from 'c' that can reach 'c' using their outgoing edges. The 'n' is configurable based on user's requirement to set for desired number of hops. The higher the number of hops, the further a particular edge's metric will be broadcasted by the RSUs. It is to be noted that, although the computational complexity of this algorithm is $O(n^3)$, it is calculated only once for a given map before the simulation run. Thus, the simulation runtime is not impacted by this algorithm's higher computational complexity.

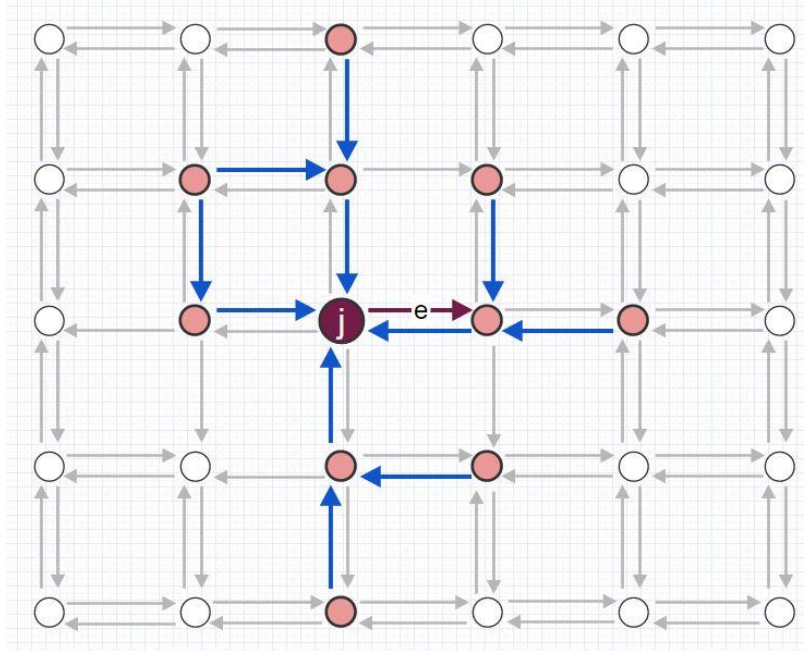


Figure 3.2 Edge-RSU relationship using $n=2$. The colored RSUs will broadcast metric value of prospective edge 'e' with start node 'j' for nearby vehicles to influence route planning

Proposed Algorithm for Edge-RSU Relation

Input:

Node set, \mathbf{V}

Edge set, \mathbf{E}

Graph $G = (\mathbf{V}, \mathbf{E})$

Max_hops = n

Result:

For any given directed edge $e (v_1, v_2)$, find node set \mathbf{A} , such that $\forall v \in \mathbf{A}$, v can reach v_1 , in n hops, using their outgoing edges, if there exists such an edge. The node set is analogous to RSU set here.

Initialize dictionary $D \leftarrow \emptyset$, for edges as key and set of associated nodes as value

For each node $v \in \mathbf{N}$ do

Initialize outgoing edge set, \mathbf{O}

Find \mathbf{O} for v such that $\forall e (v_1, v_2) \in \mathbf{O}, v=v_1$

```

for each outgoing edge,  $g \in \mathbf{O}$  do
  Initialize queue Q
  Q.enqueue ((g, 0))
  while Q is not empty do
    current_node  $\leftarrow$  Q.front.first
    hop_count  $\leftarrow$  Q.front.second
    if hop_count > Max_hops then
      Q.dequeue ()
      Continue
    if g is a key in D then
      if current_node is not in D[g] then
        Initialize temp  $\leftarrow \emptyset$ 
        temp  $\leftarrow$  D[g]
        temp.push_back (current_node)
        D[g]  $\leftarrow$  temp
      else if g is not a key in D then
        Initialize temp  $\leftarrow \emptyset$ 
        temp.push_back (current_node)
        D[g]  $\leftarrow$  temp
    Q.dequeue ()
    for each edge  $e (v_1, v_2) \in \mathbf{E}$ , do
      if  $v_2 = \text{current\_node}$ 
        Q.enqueue (v2)
    done
  done
done
done
done

```

3.1.2 Maintain Current Traffic Information

TMC plays the central role for the overall setup in our approach by calculating edge travel time and occupancy window, maintaining different table updates that can be queried by RSUs and purging obsolete information to minimize different dynamic table entries reducing query time. TMC runs in every 'tmc_run_frequency' interval indefinitely. This interval can be configured to maximize or relax the degree of precision by which the information is processed and updated in the central database.

The travel time sent by vehicles via RSU can be stored in a dynamic table – 'ttu table' in which outdated data that are no longer needed gets deleted. For each edge, TMC first looks into the 'ttu table entries' associated with that edge. It takes the latest 'n' number of entries that falls into 'm' update interval. Both 'n' and 'm' can be variable and are configurable using 'max update entries' and 'max update interval'.

<i>TMC application's high level pseudocode</i>
Start: For each edge in edge set - <ol style="list-style-type: none">I. Query travel time update entries up to the number of 'max_update_entries'II. For entries that fall in range of 'max_update_interval', calculate average travel timeIII. For entries that are queueing delay update and within 'max_udpate_interval', set average travel time equal to latest entry's travel timeIV. Calculate occupancy rate within occupancy windowV. Calculate compound metricVI. Delete outdated entries from the tablesVII. Go back to Start

The idea behind the ‘max update entries and interval’ restrictions is to limit how many table entries should be considered in calculating the average travel time and during what window these entries should be considered as valid, both in respect to the corresponding edge. These restrictions provides granular control over how recently the data that are gathered should be considered.

average_travel_time within max_update_interval

$$= \frac{\sum_{i=0}^{\max_update_entries} travel_time}{\max_update_entries} \quad (3.1)$$

During the scanning of ‘ttu table’ entries, TMC also checks if any of the entries has its ‘validity_bit’ set to 1 which indicates that the given entry’s update came from a vehicle stuck longer than 1 one ‘intersection traffic light phase cycle’ duration or, any other configurable time based on the simulation requirement. Since an ego vehicle only transmits a ‘ttu’ when it completes an edge trip, vehicles stuck in an intersection due to onward congestion never gets to transmit that. A ‘ttu update’ with its ‘validity_bit’ set to 1 solves this problem by differentiating a regular ‘ttu’ with a ‘ttu’ transmitted by a stuck vehicle. The necessity becomes more obvious when TMC considers a ‘ttu table’ entry of a particular edge without meeting the requirement of ‘max_update_entries’ as there wouldn’t be enough entries to consider during as intersection queuing delay. If TMC finds multiple entries with the ‘validity_bit’ set to 1, it considers the entry with the latest timestamp. This can be achieved by having the ‘last_timestamp’ of the entries ordered ascendingly by timestamp values of the entries.

The 'average_travel_time' is calculated using equation 3.1 and in the case where the number of entries for an edge had not reached 'max_update_entries' but there was an entry with the 'validity_bit' set to 1, the travel time posted by such entry is immediately considered and set as the travel time for that edge.

Once the travel time is calculated, an 'occupancy_rate' value is measured for given edge within the 'occupancy_window' – a time window that spans standard travel time for that edge. 'occupancy_rate' itself reflects how much length of an edge is occupied with vehicles. From empirical point of view, higher occupancy should result in longer 'intersection queuing delay' resulting in longer wait time. So, we have considered this rate to be counted in the final metric calculation of edges.

$$occupancy_window = latest_timestamp - \frac{edge_length}{edge_speed} \quad (3.2)$$

$$occupancy_rate = \frac{(vehicle_count\ in\ occupancy_window * standard_vehicle_length)}{edge_length} * 100 \quad (3.3)$$

The 'compound_metric' is finally calculated with full weight of 'average travel time' and partial weight of 'occupancy_rate'. The weight is configurable as desired by setting the value to 'occupancy_weight' variable. The rationale for not considering a full weight of 'occupancy_rate' is to cap the metric value as there exists edges of short length in simulation that can produce close to 100% occupancy rate with a few vehicles present.

$$compound_metric = average_travel_time + occupancy_rate * occupancy_weight \quad (3.4)$$

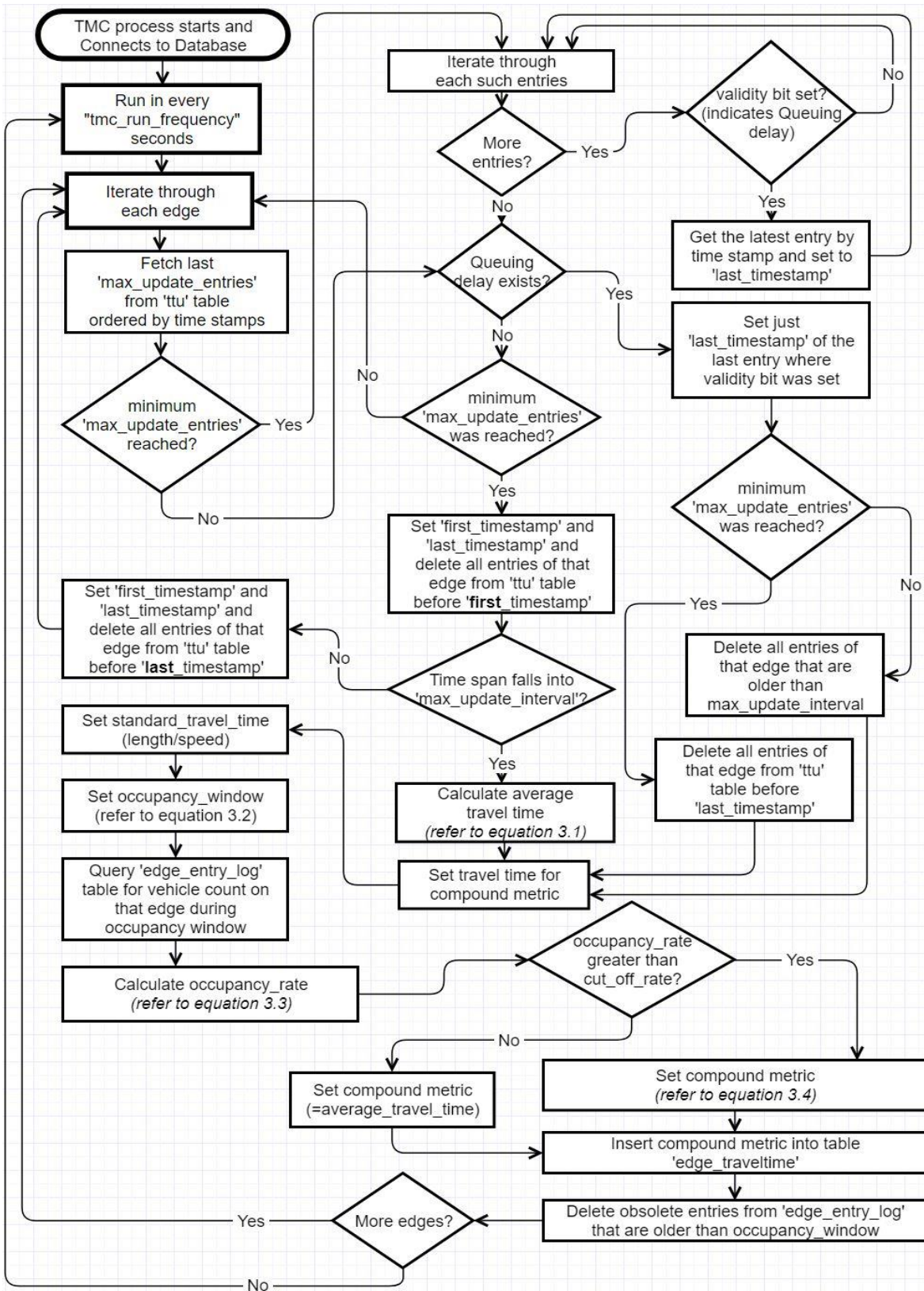


Figure 3.3 TMC process flow chart

3.2 Vehicle OBU Functionality

3.2.1 Send Travel Time Updates

As a vehicle enters an edge, it stores the 'start time' on that edge which is subtracted from the 'end time' as the vehicle completes travelling that edge for finding the travel time. On completion, it constructs 'ttu' packet that holds the travel time for last completed edge and broadcasts it over the DSRC medium. In case of last edge being empty where the vehicle just started its trip or, the last edge is an internal edge adjoining intersections, it ignores travel time calculation for that edge. The ego vehicle also keeps track of idle time on any edge to find if it's waiting more than the queuing delay threshold. The threshold in this case is a value that is configurable and ideally set to the total phase time of traffic light of the given intersections in the simulation run. If the ego vehicle is waiting over this threshold in an edge, it immediately constructs 'ttu' message without completing travel on that edge. During 'ttu' packet construction, it identifies the delay by setting the 'validity_bit' of the packet to 1. In such case, it also sets the travel time equal to the combined time it spent on that edge at idle and mobile state.

3.2.2 Update Vehicle Route

If the ego vehicle receives a 'tum' message from RSU, it creates a copy of its map (i.e. Graph) and updates the edge cost(s) as retrieved from the 'tum' message into the copied graph. It then calculates a new route using the proposed *Fuel Efficient Route Planning* (FERP) algorithm. FERP uses an A* search algorithm to calculate the 'best' route from the ego vehicle's current location to its destination. Once the new route is calculated, it submits the route as active in TraCI and discards the copied graph. The new route remains active until a new traffic update message with new

edge metric is received by the ego vehicle. Figure 3.4 depicts the high level process flow chart for the vehicle application.

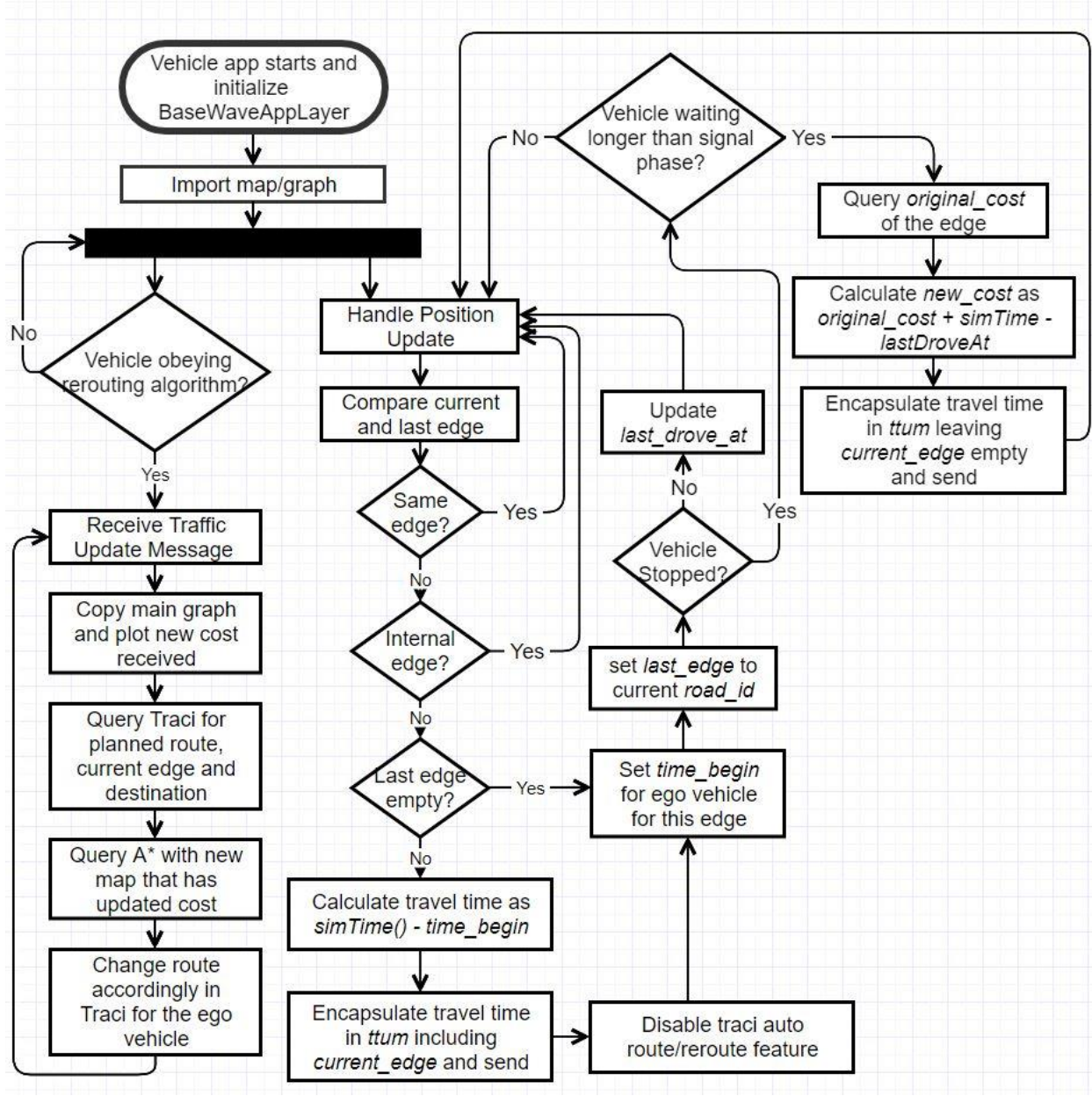


Figure 3.4 Vehicle application flowchart

A benefit of A* over Dijkstra’s algorithm use for our purpose is to limit the algorithm’s search to find shortest path only towards the specified destination. A* also overcomes

shortcoming of Greedy Best First Search algorithm (that occasionally miscalculates the shortest path) by using both actual distance from starting point and estimated distance to goal instead of just considering estimated distance alone. The proposed heuristic (FERP) uses –

$$f(n) = g(n) + h(n)$$

$$\text{where, } h(n) = |A - B| \text{ mod } l$$

Here $f(n)$ is heuristic function, $g(n)$ represents actual cost to current point, $h(n)$ is the heuristic cost to reach the destination from current point and A and B are location coordinates of current point and destination. To make the heuristic function admissible i.e. to prevent overestimation we mod of the absolute distance of two points by the shortest edge length in the simulation.

Although our implemented graph engine constructs the graph using nodes and directed edges, queries to FERP was made through both nodes and edges rather than one of them alone. The node based adjacency and construction allows the graph to store coordinates for individual nodes that are required to produce heuristic function values for FERP, whereas edge adjacency list was consulted for neighbors and shortest path trace back for reason of driving permissibility – which defines whether permission to enter an edge is valid from the current edge. This is important since, there are traffic restrictions that disallow driving from an edge to another edge. This is analogous to the real life traffic restriction scenarios such as ‘no left or right turn is allowed’. Figure 3.5 further demonstrates the scenario where $i \rightarrow j \rightarrow k \rightarrow m$ path looks promising

as there are valid edges and lower metrics, but infeasible since right turn is not allowed from edge $i \rightarrow j$ to edge $j \rightarrow k$.

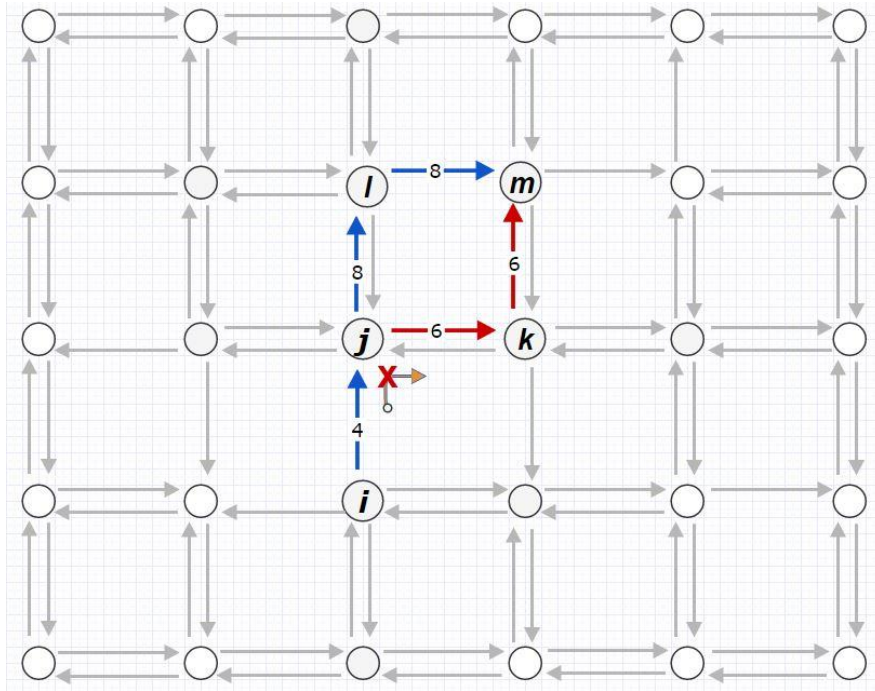


Figure 3.5 Driving permissibility is required to be consulted for correct operation of FERP

FERP algorithm pseudocode

Define 'start' and 'end' edge for source and destination

For trace back of already crossed edges, define dictionary, $\mathbf{C} \leftarrow \emptyset$

For holding minimum cost to reach an edge so far, define dictionary $\mathbf{M} \leftarrow \emptyset$

For travel time from 'start' to current edge, define \mathbf{g}

For lowest estimated travel time from current edge's end node to 'end' edge's end node, define \mathbf{h}

Define \mathbf{f} , which holds combined cost of \mathbf{g} and \mathbf{h}

For current edge, define \mathbf{c}

For holding explored edges and cost of reaching those edges, define Priority Queue, $\mathbf{Q} \leftarrow \emptyset$

$\mathbf{Q}.\text{enqueue}((\text{start}, 0))$

```

C[start] ← none
M[start] ← 0
While Q is not empty do
    c ← Q.dequeue ( )
    if c is 'end' then
        break
    for each driving permissible neighbor k of edge c do
        g ← M[start] + actual cost to reach k from c
        If k is not in M and g < M[k] then
            M[k] ← g
            f ← g + h(k, end)
            Q.enqueue(k, f)
            C[k] ← c

```

3.3 RSU Functionality

RSU application is hosted in the fixed RSU nodes in selected junctions as will be described in section (4.1.5). It acts as a bridging point for receiving 'ttu' packets from nearby vehicles and transfer them over to TMC for processing. Once the application is initialized and connection to TMC's database is made, RSU application processes two kind of messages. The first type is a self-message set at predefined regular interval which prompts a given RSU to query TMC's database for metric updates of edges that the RSU is responsible for. If metric updates are available, the metrics are encapsulated in 'tum' message and broadcasted over the DSRC medium. The second type is a 'ttu' message broadcasted by an ego vehicle. The 'ttu' message contains information of a vehicle's entry timestamp to the current edge, travel time for previous edge and whether the travel time posted is a result of queuing delay experienced by the vehicle. These information are

updated to the TMC's database for further analysis. A high level process flowchart for this application is depicted in figure 3.6.

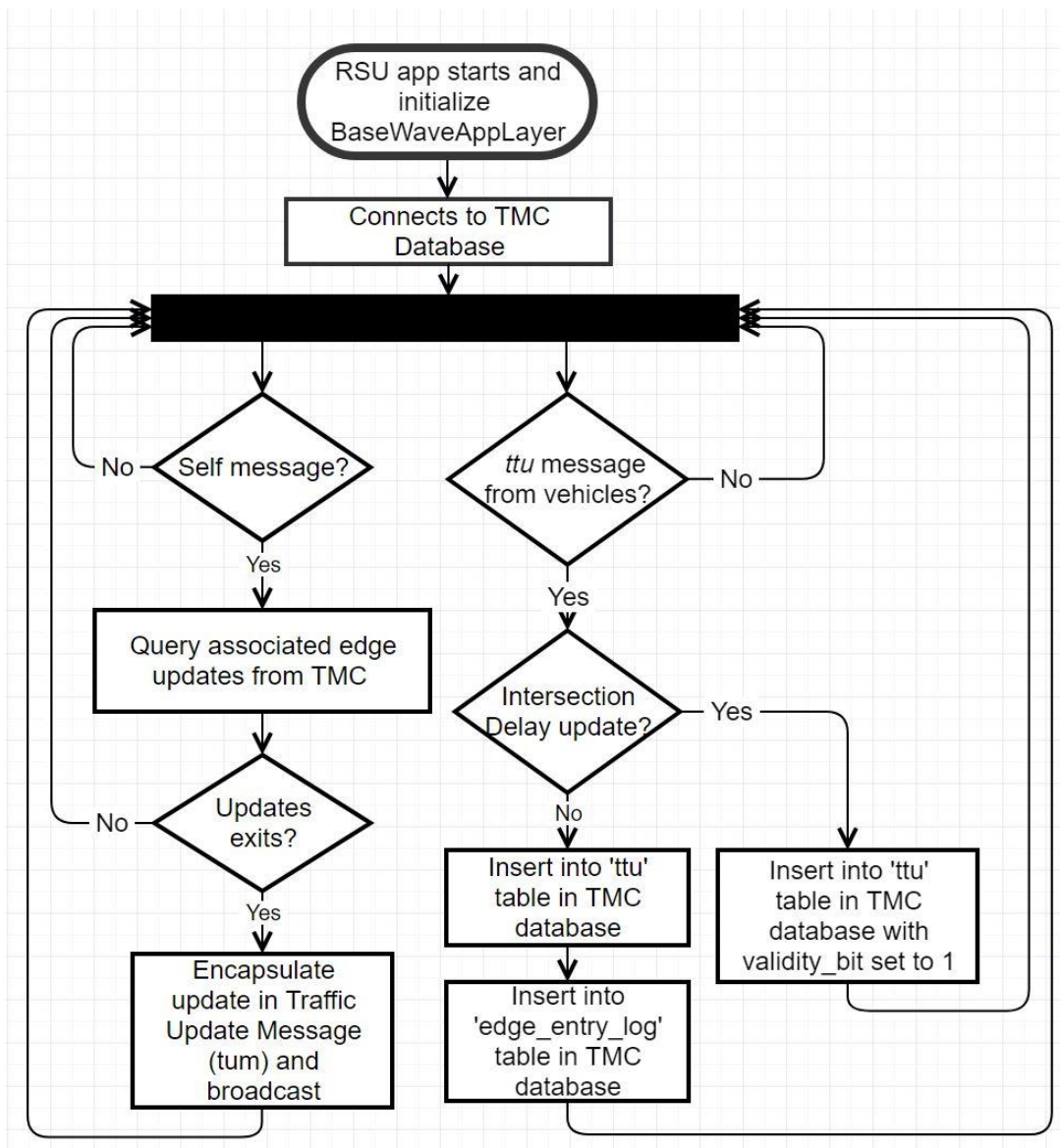


Figure 3.6 RSU application process flowchart

4. Experiment Setup and Results

4.1 Experiment Setup

To experiment our proposed approach, we used three simulation tools, SUMO, OMNET++ and VEINS as introduced in section 2.2. For traffic generation, SUMO requires a set of xml files that describes the road network and traffic demand. The network file also needs to be converted to graph form so the vehicle application can query routes using A* algorithm. In the following subsections, we will describe the processes used for extracting necessary files for the experiment setup. Table 4.1 introduces some terminologies that will be used in the following sections.

Table 4.1 Notations used in experiment

Notation	Description
'.net'	Used by SUMO to realize map database
'.osm'	Open Street Map file extension
NETCONVERT	A python script that generates 'net' file from .osm format
'xml_to_txt.py'	A python script that extracts sets of relevant junction and edge parameters from the 'net' file.
'.ned'	Network descriptor file used by OMNET to define parent and sub modules of the network simulation
'.ini'	An initialization file that describes parameters for modules defined in '.ned'
'omnet_coord.txt'	Text file containing OMNET specific coordinates of junctions
'traci_coord.txt'	Text file containing TraCI specific coordinates of junctions
'inter_junction_finder.py'	A python script that selects candidate junctions from 'net' file for RSU placement
'junc_coord_extract.py'	A python script that generates RSU coordinates in format acceptable to '.ned' and '.ini' files

'graph_input.txt'	produced by 'xml_to_txt.py' script and used for graph construction
'rsu_junction_bind.txt'	Text file containing junction id and RSU id pairs
'Edge_RSU_Relation.h'	An application that associates edges to RSUs in a many to many relationship and exports the relationship into TMC's database
'VEINS Extraction Run'	A simulation run in which 'omnet_coord.txt' and 'traci_coord.txt' files are created and populated. Actual vehicle simulation run is skipped
'VEINS Simulation Run'	Vehicles are simulated in this run

4.1.1 '.net' file generation

.net file is an XML file that mainly defines how the junctions and edges are associated, what are the connections between edges and between internal and external edges, what lanes are available to each edges and their types, direction and permissions. The .net file is generated using the NETCONVERT tool where input is a 4x4 square kilometers of University of Windsor's surrounding area map with .osm extension (OSM stands for Open Street Map). In our simulation, the .net file is processed using 'xml_to_txt.py' python script.

4.1.2 Graph node and edge extraction

The 'xml_to_txt.py' script extracts the XML elements using python's 'ElementTree XML library' and produces three text files as output – 'graph_input.txt', 'graph_edges.txt' and 'edge_adjacency.txt'. These output files are then processed using other scripts and graph engine (a C++ file that maintains the graph) for graph creation and references to adjacencies of nodes and edges. In our simulation, junctions represent graph nodes and roads represents graph edges.

4.1.3 Internal junction and edge elimination

Connectivity between lanes through junctions are defined using internal junctions and internal edges and these falls under the same tree element in the .net file as normal junctions and edges. These internal junctions and internal edges are eliminated during the processing of the three above mentioned output files by the 'xml_to_txt.py' python script since they will not be used during graph construction. Also, edges that are only for pedestrians, trams, rails and bicycles are also eliminated during processing of output files since vehicles will avoid those routes.

4.1.4 Node, edge and RSU association, and driving permissibility

The graph engine maintains 'list of nodes' as junction dictionary and 'list of edges' that holds the junction pairs to form directed edges between them. In addition, an 'edge adjacency list', constructed by the 'xml_to_txt.py' script, is maintained that determines whether an edge is associated to another edge in terms of 'driving permissibility' - as described in section 3.2.2. Also, this 'edge adjacency list' filters out the edges that are dead ends and as such, those edges are not associated with any other edges. The 'Edge_RSU_Relation.h' from the graph engine takes care edge-RSU association using our proposed algorithm in 3.1.1.

4.1.5 RSU placement selection

RSUs are placed at every junctions except where the junction itself represents node of a dead-end edge. This is done through the use of a python script 'inter_junction_finder.py' which produces a text output file 'inter_junction.txt'. The text output later used by another python

script 'junc_coord_extract.py'. The purpose of this script is to define the placement of junction definitions according to the corresponding formats acceptable by .ned (Network Descriptor) and .ini (OMNET initializer) files. When producing the formats, the 'junc_coord_extract.py' script cross reference 'inter_junction.txt' file for selecting the junction set for RSU placement that intersects with the set of junctions listed in the text file.

'junc_coord_extract.py' script also takes two other files as input – 'traci_coord.txt' and 'omnet_coord.txt', for the purpose of producing corresponding coordinates accepted by the .ned and .ini files mentioned above. The differences in such coordinates between OMNET and SUMO for any point in the playground (the area where simulation runs) comes from the fact that the point of origin for each systems are calculated differently. Thus an RSU's placement coordinates that works for SUMO will not work for OMNET and hence needs the above adjustment. The text files 'traci_coord.txt' and 'omnet_coord.txt' are produced by Car node's extraction run which will be explained in section 4.1.8.

4.1.6 Database setup

MySQL version 4.1 is used for simulation parameter recordings as this version integrates well with OMNET++. A series of pre-configured signals is emitted during simulation run from OMNET++ which subsequently gets captured by 'cMySQLOutputVectorManager' and 'cMySQLOutputScalarManager' libraries of OMNET++. The captured signals are recorded directly in vector and scalar form into the MySQL's 'test' database.

While the simulation vector data and scalar data such as trip time, CO₂ emission, speed, acceleration etc. automatically gets recorded into 'test' database during simulation runs, an additional database named 'traffic_monitoring_center' records data sent by RSUs and data processed by TMC application. It is to be noted that CO₂ emission is calculated by VEINS using statistical model proposed in [30].

Table 4.2 Tables used in the database

Table	Purpose
'all_edges'	Holds edge properties such as 'edge_id', length and speed
'edge_entry_log' *	Timestamps of vehicles entering edges, for 'occupancy_rate' calculation
'edge_traveltime' *	Edge metrics for broadcasting
'junction_edges'	Edges that a junction's RSU is responsible for
'rsu_junctions'	RSUs to junctions bindings
'ttu' *	Travel Time Update for respective edges

** indicates entries are dynamically saved and purged*

4.1.7 TMC setup

TMC application is developed using C++ and it interfaces with central database hosted in MYSQL. As updates are pushed from RSUs to the central database interfacing TMC, TMC process the updates through a series of steps described in section 3.2 to acquire relevant information, store the information into relevant tables which in turn will be queried by RSUs for dissemination. Figure 4.1 shows the high level setup for TMC and its interaction with other components.

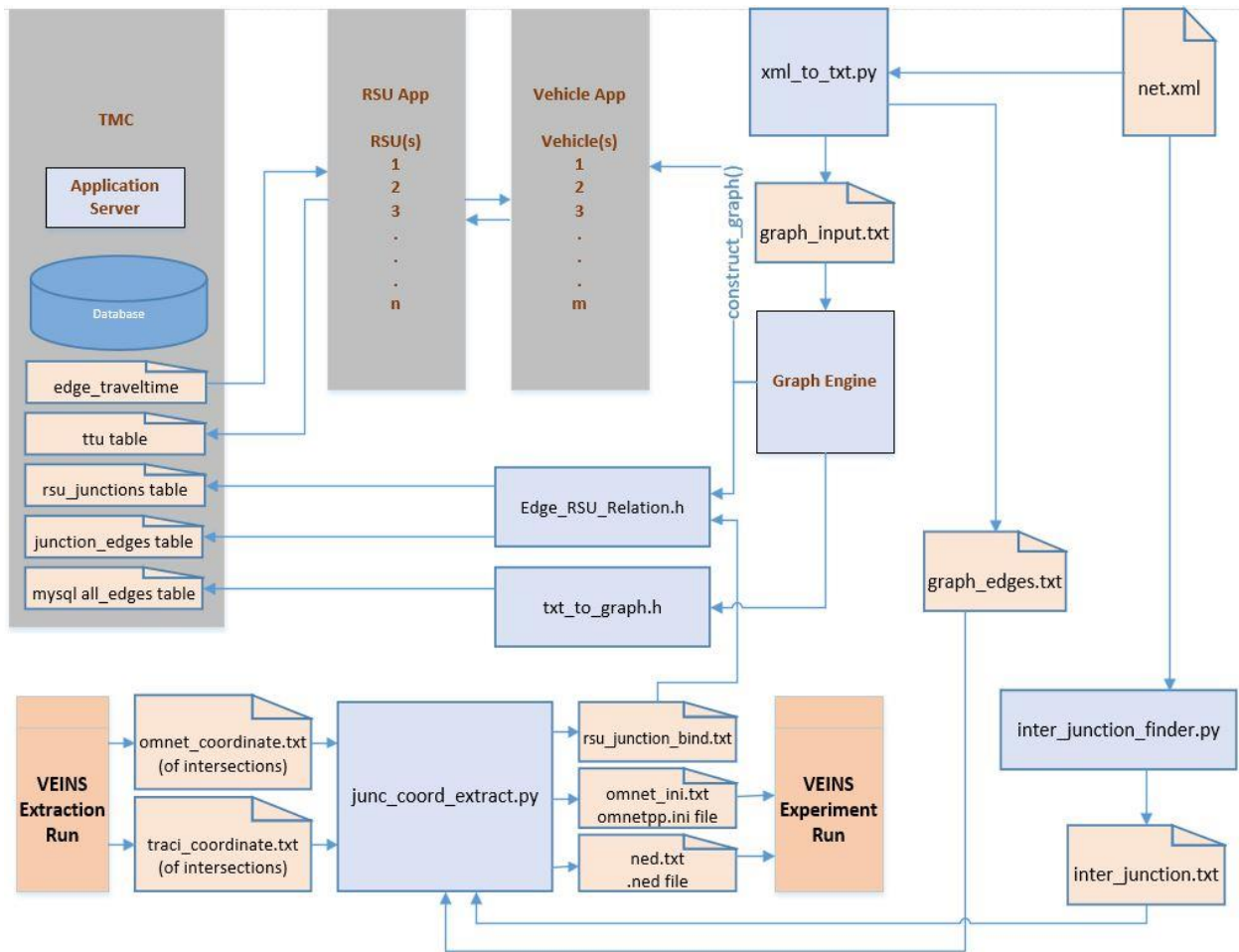


Figure 4.1 High level setup of the experiment

4.1.8 Vehicle setup

Vehicle application is a C++ program that defines the behavior of a vehicle during simulation run. In addition to that, this application also facilitates extracting OMNET++ and SUMO coordinates for RSU placements as they are differently setup and have different values for corresponding .ini and .ned files described earlier in section 4.1.5. In the application itself, an ego vehicle can query TraCI server of SUMO for any vector values that are function of the simulation

time such as speed, acceleration, current edge etc. along with other simulation parameter values using VEINS internal framework tool known as 'TraCICommandInterface'.

4.1.9 Vehicle – RSU interaction

Vehicles interact with RSU using two types of messages – 'ttu' (Travel Time Update) and 'tum' (Traffic Update Message). 'ttu' is sent by the ego vehicle to advertise the last completed edge's travel time whereas 'tum' is sent by the RSUs to advertise travel time information of a set of prospective edges that the ego vehicle can choose for its route planning. Both of these messages are an extension of WSM (Wave Short Message), which is the default message type from the WAVE protocol stack using WSMP protocol. The messages add relevant information such as completed edge ID, current edge ID, travel time, vehicle ID etc. based on the message type before encapsulation down to MAC layer for transmission over 802.11p medium.

4.1.10 Route file / Demand generation

Route file describes when and which vehicles are inserted into the simulation containing predefined edges to be taken. In our experiments, we have used route file generated by SUMO's built in script 'randomtrips.py' where the input is University of Windsor's surrounding area's .net file. Two route files were generated for experiment – first, with an insertion rate of 1 vehicle per 0.20 second and insertion window of 0 to 400 seconds of the simulation run and second, with an insertion rate of 1 vehicle per 0.15 second and insertion window of 0 to 500 seconds of the simulation run. A 'fringe factor' of 10 is used during the demand generation which indicates

source and destination of demand routes are 10 times more likely to be on the map edges rather than on the center of the map.

4.2 Results

We have run two sets of simulations with the scenario summarized in table 4.3. The first set of runs was with 2500 vehicles and the second set of runs with 3300 vehicles. With the first set as shown in table 4.4, we found the best result with the combination of 55 seconds queuing delay and 2 hops of Edge-RSU relationship. Since the improvement was marginal, we run the second set of simulations with 3300 vehicles to put more stress into the road network.

Table 4.3 Summary of simulation properties

Number of edges for vehicles	465
Total edge length for vehicles	98.09 km
Number of RSUs	200
EDGE-RSU associations with 2 hops	4230
EDGE-RSU associations with 3 hops	7536
EDGE-RSU associations with 4 hops	11579
EDGE-RSU associations with 5 hops	16171
RSU query TMC at every	4 sec

With the second set as shown in table 5.5, we found the best result with the combination of 55 seconds queuing delay and 5 hops of Edge-RSU relationship. This resulted in 8% decrease in CO₂ emission and 21% decrease in aggregated trip time for all vehicles ran in the simulation.

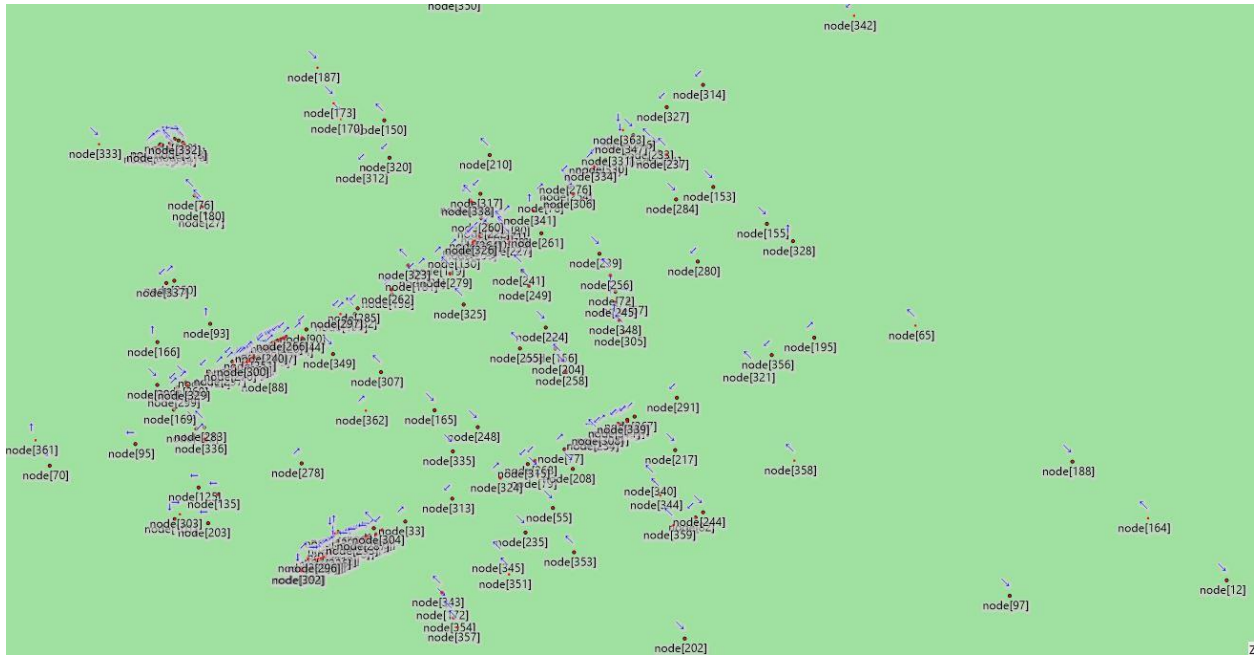


Figure 4.2 Screen capture of the simulation run from OMNET++

We compared this best result without the presence of queuing delay factor. The result shows with queuing delay factor we can achieve better efficiency in terms of aggregated trip time and CO2 emission. The result is summarized in table 4.6.

Table 4.4 Result of setup 1

Setup 1				
Number of vehicles 2500 with insertion window 0 - 400 sec				
Dynamic Route planning	Queuing Delay	Edge-RSU relationship	Aggregated trip time of all vehicles (in seconds)	Total CO2 emission
No	No	2 hops	82835	283836.58
Yes	35 seconds	2 hops	112206	309496.65
Yes	45 seconds	2 hops	104263	295971.14
Yes	55 seconds	2 hops	81996	279397.81
Yes	65 seconds	2 hops	81493	279068.95
Yes	75 seconds	2 hops	96870	294694.28

Table 4.5 Result of setup 2

Setup 2				
Number of vehicles 3330, insertion window 0 - 500 sec				
Dynamic Route planning	Queuing Delay	Edge-RSU relationship	Aggregated trip time of all vehicles (in seconds)	Total CO2 emission
No	No	N/A	193701	508309.84
Yes	45 seconds	2 hops	157452	474846.65
Yes	55 seconds	2 hops	171688	490034.15
Yes	65 seconds	2 hops	157552	476243.29
Yes	75 seconds	2 hops	166634	480298.64
Yes	45 seconds	3 hops	154439	470269.69
Yes	55 seconds	3 hops	151234	465187.23
Yes	65 seconds	3 hops	157005	474678.55
Yes	75 seconds	3 hops	174675	491239.55
Yes	45 seconds	4 hops	159098	474087.41
Yes	55 seconds	4 hops	159626	474617.39
Yes	65 seconds	4 hops	197380	521643.51
Yes	75 seconds	4 hops	209215	534864.04
Yes	45 seconds	5 hops	176426	497980.34
Yes	55 seconds	5 hops	151673	464810.08
Yes	65 seconds	5 hops	190239	509266.38

Table 4.6 Performance comparison with no dynamic route planning and no queueing delay

Dynamic Route planning	Queuing Delay (in seconds)	Aggregated trip time of all vehicles (in seconds)	Total CO2 emission	Decrease in aggregated trip time (%)	Decrease in Total CO2 emission (%)
Yes*	No	170034	484709.77	12.22	4.64
Yes*	55 seconds	151673	464810.08	21.70	8.55

** With 5 hops of edge-RSU relationship and with 3300 vehicles*

5. Conclusion

In this thesis we proposed a three-tiered architecture for travel data collection, analysis and dissemination using DSRC's WAVE stack implementation. In addition, 1) we have considered the queuing delay factor in intersection and used average travel time and occupancy rate for calculation of edge metric, 2) we have offloaded the task of route planning to vehicle OBUs instead of a central entity and 3) we have proposed an algorithm that determines the area of propagation for data that needs to be disseminated by RSUs. We have tested our approach with 2, 3, 4 and 5 hops of edge-RSU relationship and with a range of 45 to 75 seconds queuing delay. Our results shows an improvement of 21% decrease in aggregated trip time and 8% decrease in CO₂ emission for 3300 vehicles running in a 4x4 square kilometers of city area with dynamic route planning and queuing delay when compared with the setup with no dynamic route planning and queuing delay.

5.1 Future Work

Our approach was tested using VEINS framework with an input area of 4x4 square kilometers. A larger size map area can be considered in future works to test the scalability of the proposed approach. In addition, an average traffic light phasing duration was used to estimate queuing delay threshold for all edges in the scenario. In real world, traffic light phase durations vary depending on the intersection size and vehicle flow. Thus, the threshold beyond which an ego vehicle should consider itself to be stuck in an intersection should vary too. Future work can

consider some mechanism for finding this threshold value on a per intersection basis rather than using an average one which should improve accuracy of edge metric calculation. Furthermore, the process of finding an optimal edge-RSU association value based on any given map that can achieve maximum route planning efficiency without oversubscribing the channel bandwidth may also be an informative future study for VANET based route planning.

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