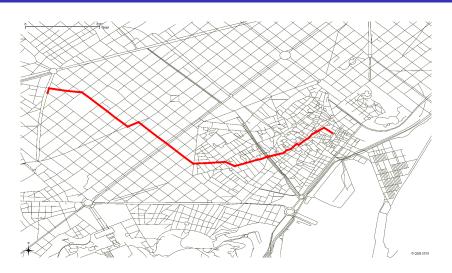
Multimodal and multi-criteria shortest paths in transportation networks

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Introduction



Shortest path problem on a road network

Let G be a graph with n vertices and m edges.

Direct methods

• Dijkstra: $\mathcal{O}(m \cdot \log n)$

• Bellman Ford: $\mathcal{O}(m \cdot n)$

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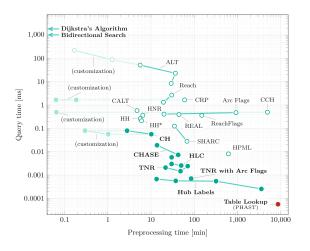
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Speed-up

- landmarks: compute shortest distances from everyone to a well chosen subset of vertices
- separators: efficient for planar graphs
- contraction hierarchies: efficient for low tree-width graphs
- and many others.





Comparison of different methods [Bast et al., 2016]

Western Europe: 18.0 millions vertices and 42.5 millions edges

Generalisation

Multimodal multi-criteria shortest paths

We want to take into account:

- other transportation means (foot, bicyle, bus, train, plane, ...)
- individual preferences (fast, cheap, easy, ...)

This emphasizes several issues:

- huge graphs
- data are collected by different providers: trade-off queries/uncertainty.

Multimodal

Temporal graphs

• Edges available at precise times! Two ways to represent it:



One-time edges

Dependent-time edges

- Dijkstra-like algorithms [Dibbelt et al., 2013]
- Same speed-up technics, but less convincing improvements.

Multimodal

Temporal graphs

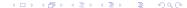
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Merging graphs

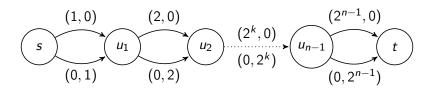
Two types of transportation: time dependent and time independent.

Problem: how to modelize a "union graph" ? No consensus

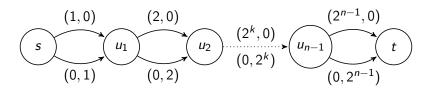
Exemple: public transportation graph with small foot complete graphs [Wagner and Zündorf, 2017]



- Compare time, costs, transfert number, ... $\Longrightarrow d$ dimensions,
- Goal: obtain non dominated solutions (Pareto Set),
- Problem: too many solutions ! If Δ is the maximum degree, possibly Δ^n solutions.

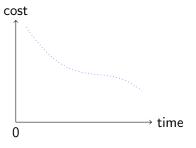


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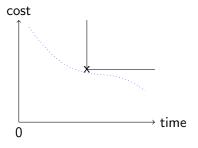


→ Approximation: cover the solution set.

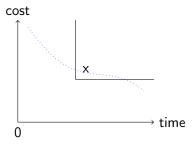
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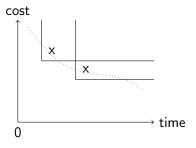
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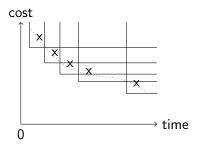
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Problem: for an $(1+\epsilon)$ precision, existing algorithms are exponential with respect to d:

$$\mathcal{O}\left(n^d \cdot m \left(\frac{\log(nK)}{\epsilon}\right)^{d-1}\right)$$
 [Tsaggouris and Zaroliagis, 2009]

Conclusion

Current work

We are trying to find a fully polynomial algorithm. Ideas so far: either correct or exponential.

Future work

- distributed aspects,
- uncertainty

The end!

Thanks for your attention !

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- [4] George Tsaggouris and Christos Zaroliagis. Multiobjective optimization: Improved fptas for shortest paths and non-linear objectives with applications. *Theory of Computing Systems*, 45(1):162–186, 2009.
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