

Modeling, Simulation and Control of Traffic Flows on a Highway Network

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Introduction



Our research aims at improving the Belgian traffic situation through the development of a flexible testbed environment. By implementing *control measures* and *predicting future traffic conditions* we are able to *resolve congestion* on a highway road network.

A *three-stage plan* is used to obtain our goals: (1) building a traffic flow model, (2) simulating the road network and (3) controlling and predicting the future traffic state.

1) Building a Traffic Flow Model

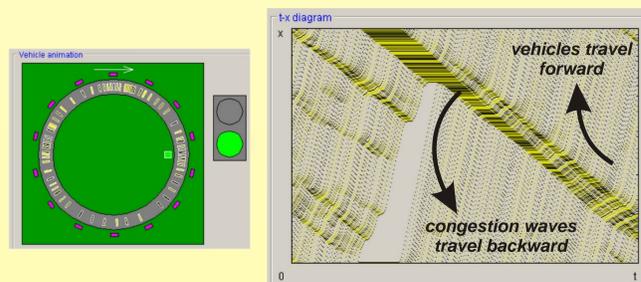
In traffic flow theory, three different classes exist for the modeling phase:

macroscopic models: based on a *fluid-dynamical* analogy, implemented using partial differential equations (large space/time discretizations used).

mesoscopic models: like macroscopic models, but instead based on a *gas-kinetic* analogy.

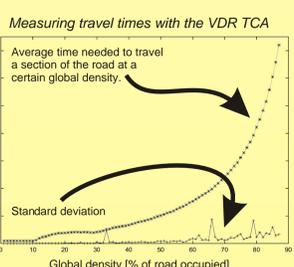
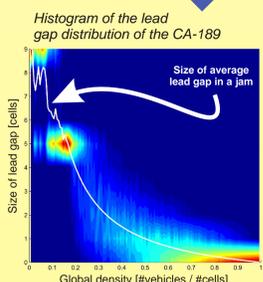
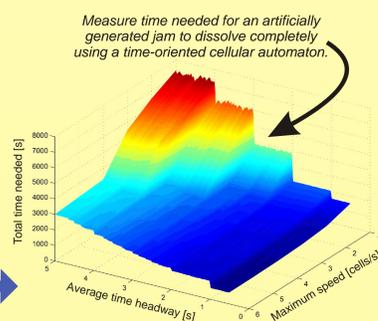
microscopic models: each vehicle in the traffic stream is considered individually. *Car-following* and *lane-changing* dynamics need to be modeled explicitly (highly computationally intensive).

An efficient implementation that is computationally feasible for large-scale networks are **traffic cellular automata (TCA)**.



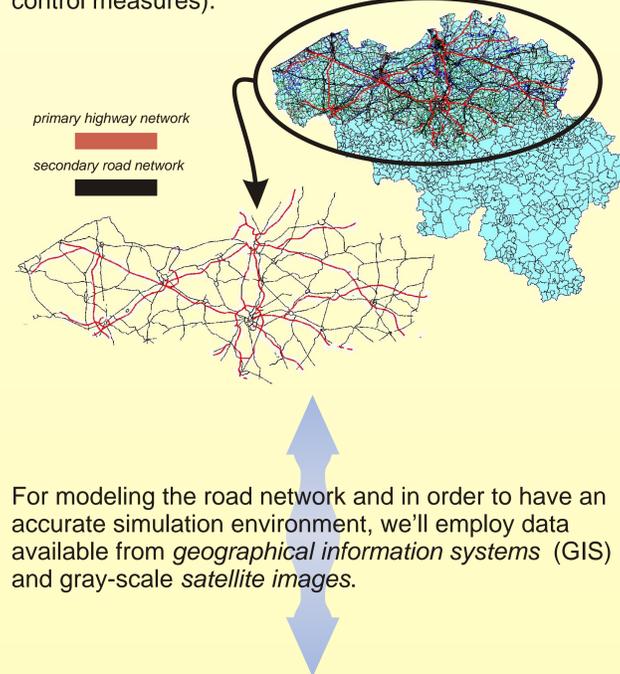
We'll develop a *rule-based* traffic flow model that incorporates the current expertise and solves several classical deficiencies. Car-following and lane-changing dynamics establish the model's core functionality; they both consist of *rule-sets* that describe the system's global behaviour in terms of movements of its individual components.

In order to tune the model for realistic behaviour, *different qualitative measures* can be implemented for *testing purposes*.

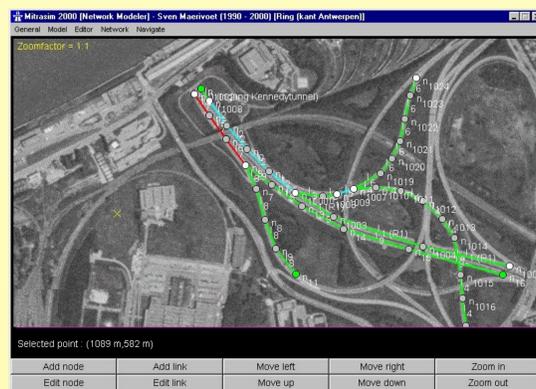


2) Simulating the Road Network

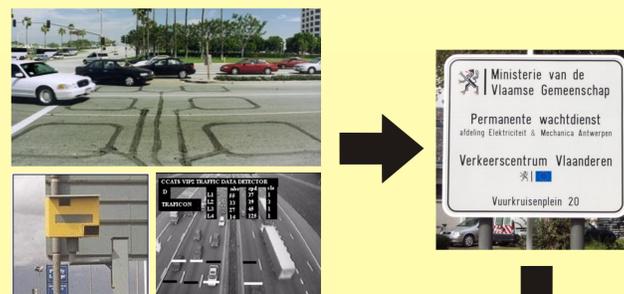
After construction of the cellular automaton, the next step will be to use this traffic flow model in a real-life network environment. The scope is the *Flemish primary highway network*, as well as its *secondary national road network* (which should be considered as a fall-back option for control measures).



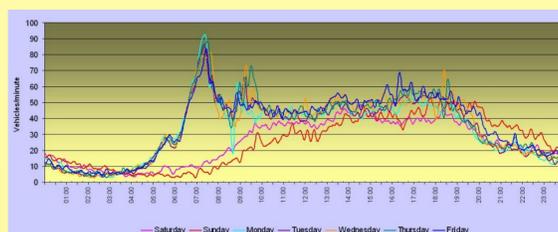
For modeling the road network and in order to have an accurate simulation environment, we'll employ data available from *geographical information systems (GIS)* and *gray-scale satellite images*.



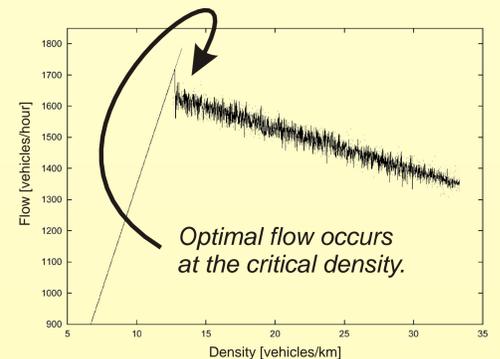
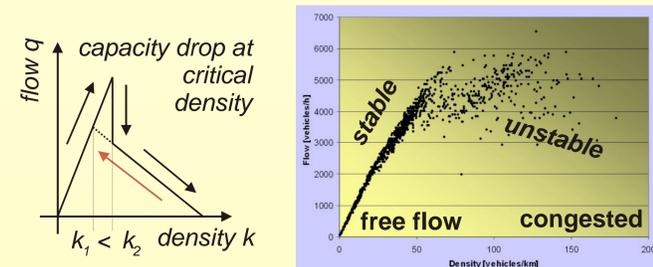
All the traffic data needed for real-time simulation is gathered by sensors in the road network and stored in a database by *Flanders' Traffic Centre*.



This database contains the macroscopic measurements as *time series* (sampling interval is 1 minute).



From the time series (used in the *calibration* and *validation* of the traffic flow model), we can construct the so-called *fundamental diagrams*. Similar to the real world, our simulation model will exhibit *metastability*, as well as a *hysteresis* phenomenon when traffic is recovering from congestion.



3) Control and Prediction

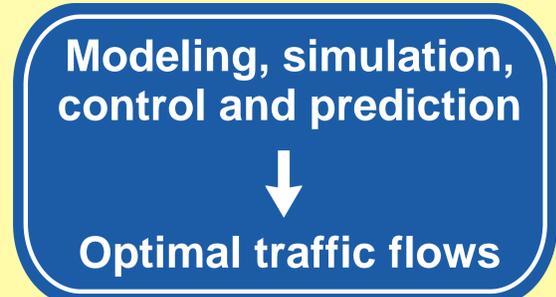
In order to *guarantee optimal traffic flows*, we'll investigate the use of *traffic control measures* such as ramp metering, variable speed limits, adaptive rerouting, ...



Advanced ramp metering can be very effective when implemented using *model predictive control (MPC)*.

Prediction of future traffic states is studied using several mathematical techniques, for example:

- the use of (partial) autocorrelations together with historical and actual data,
- model identification, regression techniques, eigen-profile analysis, dedicated datamining techniques,
- spectral analyses of the time series,
- nonlinear modeling techniques (e.g. LS-SVMs),
- attractor reconstruction using embedded delay coordinates, recurrence plots and recurrence quantification analysis,
- correlations with 'external' datasources such as climatological data, road incident statistics, ...



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For more information, please refer to <http://dwtc-cp40.dyns.cx>



For further information

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Winner of the Faculty of Engineering PhD Symposium 2002 "Best Poster Award"