COMPLEXITY METHODS FOR PREDICTIVE SYNCHROMODALITY (COMET-PS)

Frank Phillipson PDEng PhD

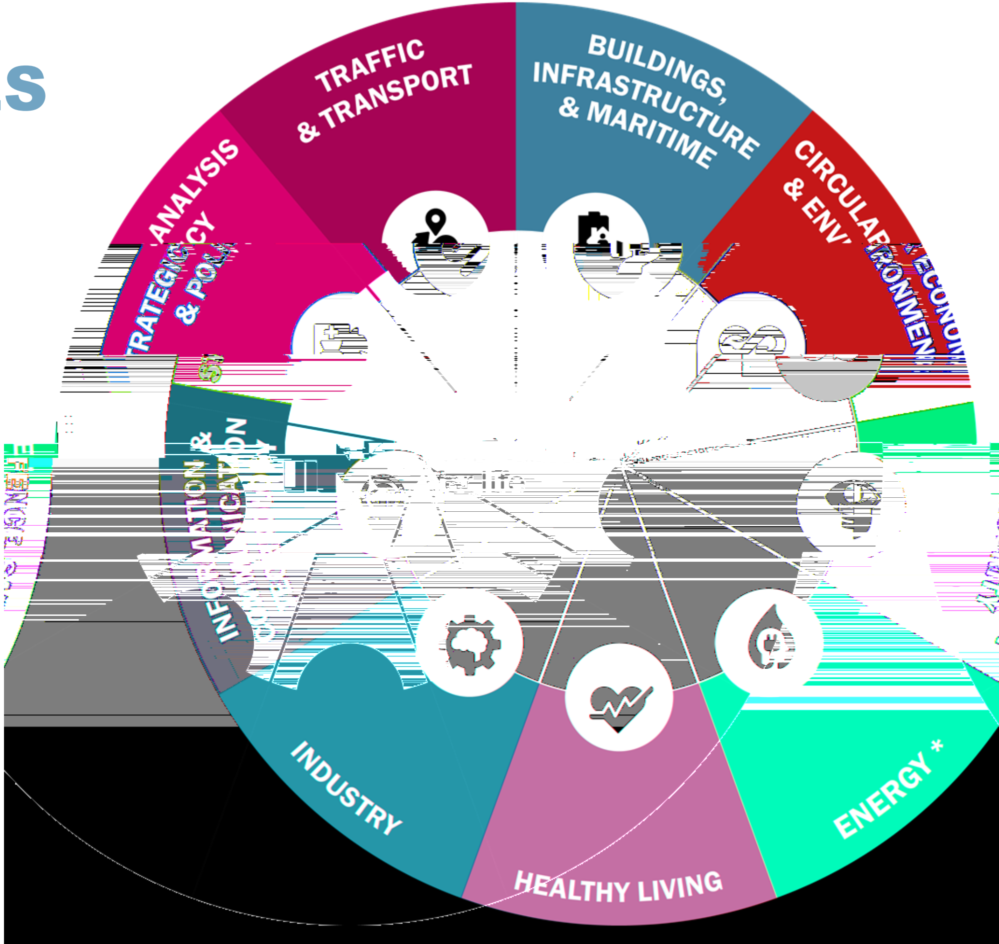
TNO innovation for life

TU Delft

TNO – APPLIED SCIENCES

‘Organisation for Applied Scientific Research in the Netherlands’:

- Founded by law in 1932.
- To enable business and government to apply knowledge.
- Independent: not part of any government, university or company.



COMPLEXITY METHODS FOR PREDICTIVE SYNCHROMODALITY

Goal: Enable a streamlined logistic system with improved transport efficiency, higher loading rate of vehicles, less emissions and costs, making use of complex synchromodal network optimization.

Funded by: NWO, TKI DINALOG, TNO, CTT

Partners:

CWI Centrum Wiskunde & Informatica
TU Delft
UNIVERSITY OF TWENTE.
TNO

Knowledge partners

CTT INTERMODAAL TRANSPORT
Port of Amsterdam
TKI DINALOG Dutch Institute for Advanced Logistics
TATA STEEL

Co-financers (through cash in kind)

Port of Rotterdam
Schiphol Group

Supporters

WHAT DID WE PROMISE?

- A prototype of a synchromodal planning system
  - well documented and supported by several (scientific) papers.

- Evaluated on real cases that have different freight characteristics like:
  - Bulk and container transport.
  - Net centric versus freight centric.
  - High and low level of uncertainty.

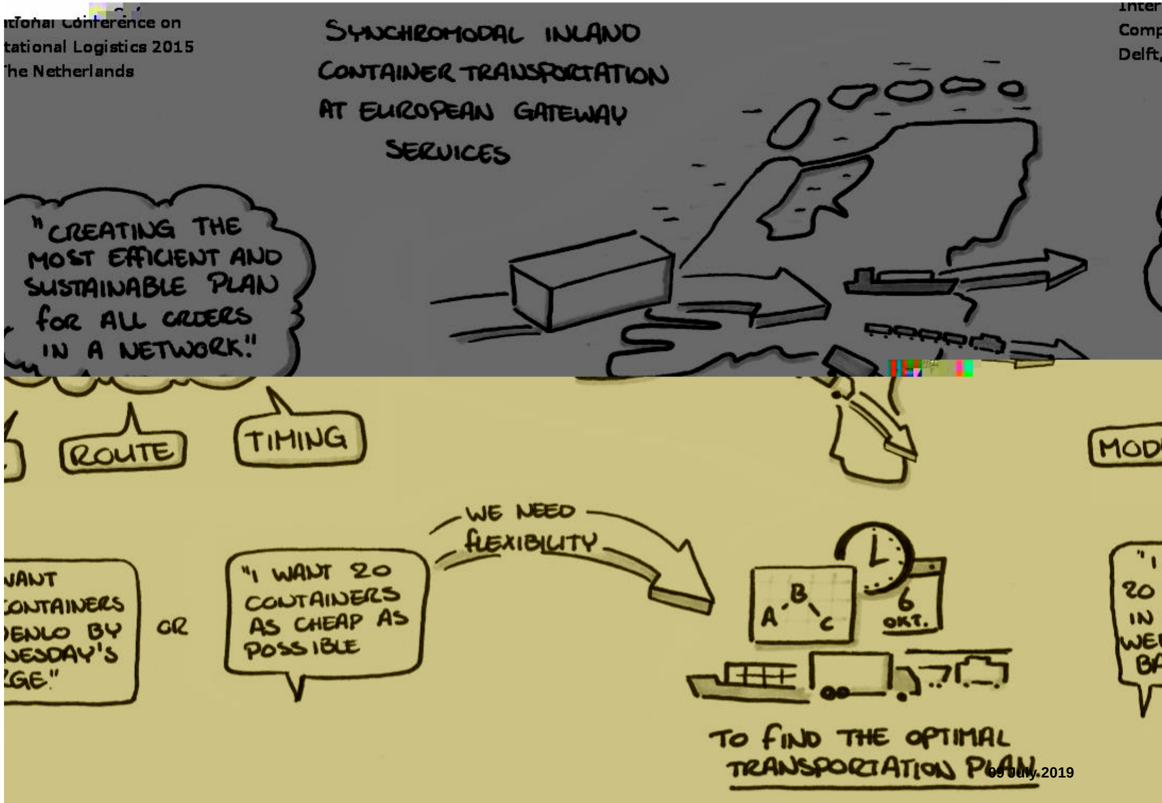
- Predictive Synchromodality: incorporating models, methods and tools based on *predictive data analysis and stochastic decision making in (distributed) control environments.*

SYNCHROMODAL TRANSPORT

From inter-modal to synchro-modal means:

1. Clients will only tell the logistics service provider when and where their cargo needs to arrive, entrusting the logistics service provider to determine how it gets there;

2. Planners will use data that is (more) real-time, and routes will become subject to change in real time when beneficial.



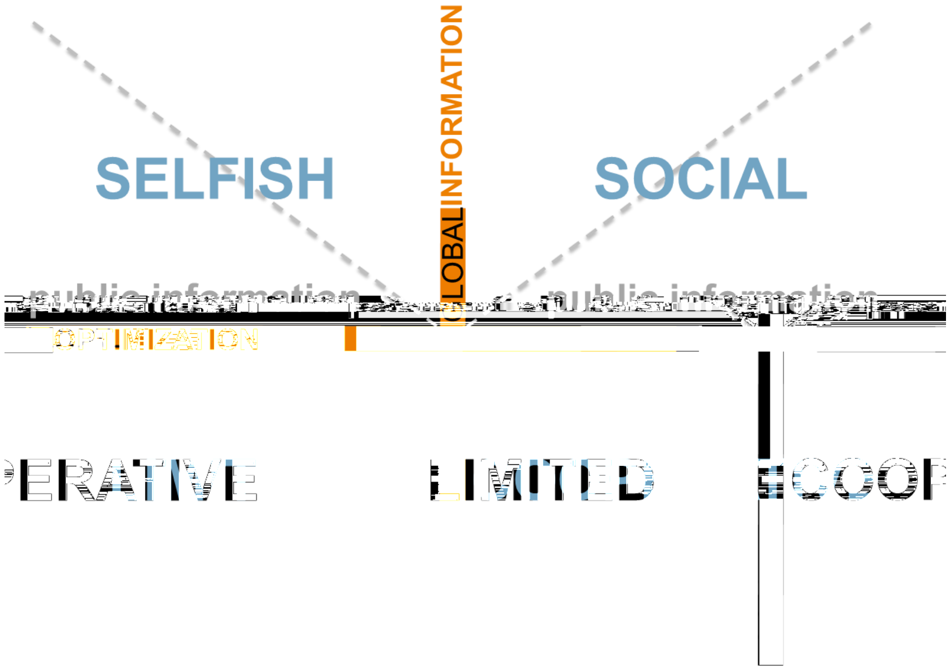
SYNCHROMODAL PLANNING

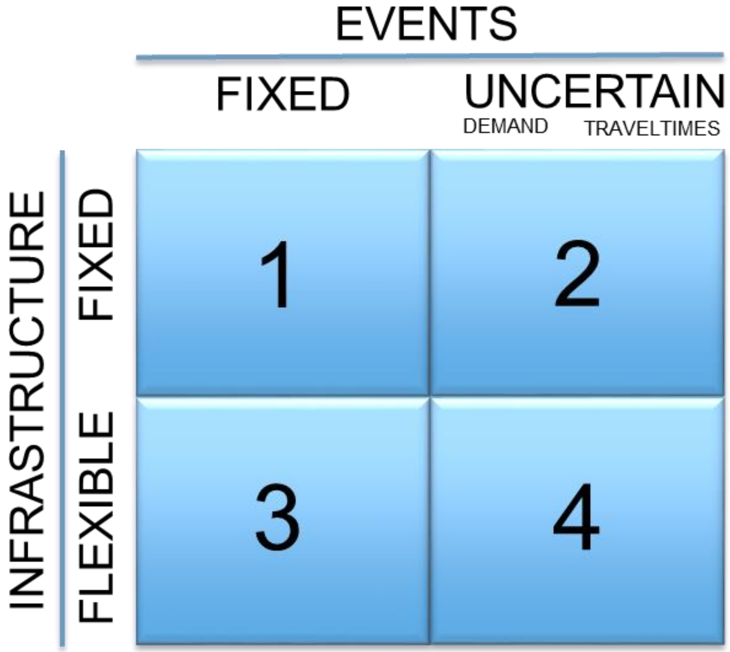
- Planning is based on data that is (more) real-time, and routes will become subject to change in real time when beneficial.

- This could mean:
  - A lot of re-planning – need for fast planning methods
  - Robust planning
    - Stochastic;
    - Worst case / robust optimization;
    - Define robustness and use as objective;
  - Decentralised planning / Distributed control
  - Self-organisation
  - Use of predictions / *predictive data analysis*

THE ROAD TO PREDICTIVE SYNCHROMODALITY

THOUGHT-FRAMEWORK





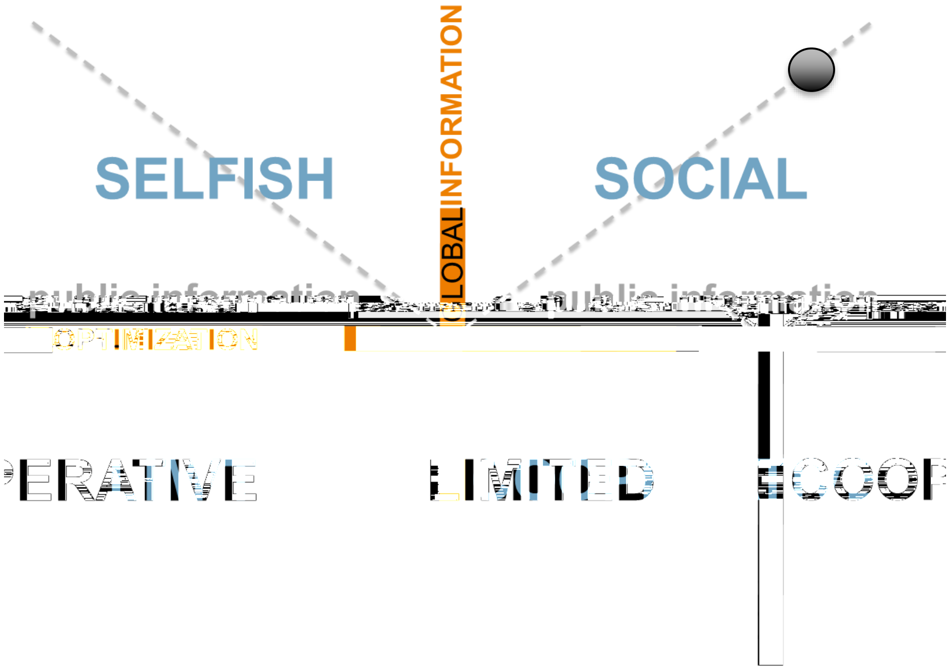
THREE PAPERS FROM COMET-PS ACCEPTED

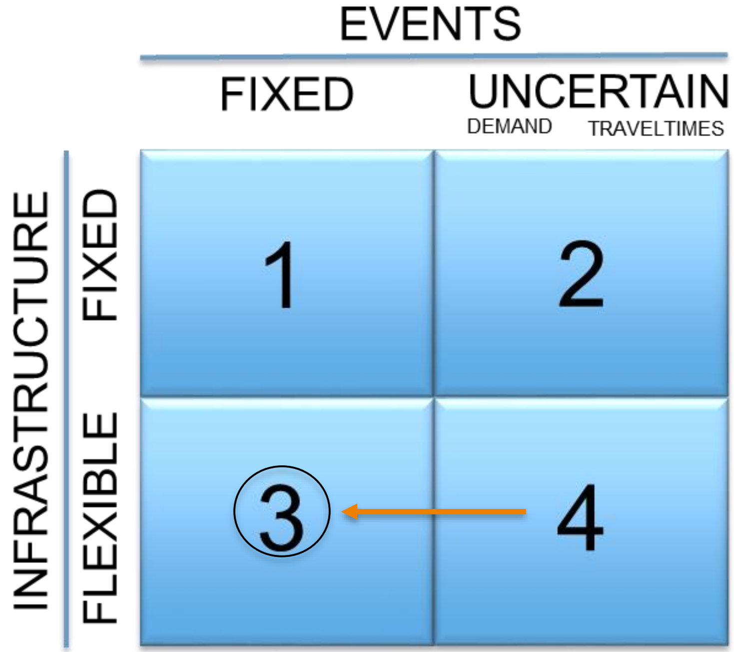
- *Reduction of Variables for Solving Logistic Flow Problems.*
  K. Kalicharan, F. Phillipson, A. Sangers, M. De Juncker

- *Decision making in a Dynamic Transportation Network: a Multi-Objective Approach*
  M.R. Ortega del Vecchyo, F. Phillipson and A. Sangers

- *User Equilibrium in a Transportation Space-Time Network*
  L.A.M. Bruijns, F. Phillipson and A. Sangers

PAPER 1: *REDUCTION OF VARIABLES FOR SOLVING LOGISTIC FLOW PROBLEMS.*





A lot of re-planning – need for fast planning methods

1 IMPROVED EFFICIENCY OF SOLUTIONS FOR DETERMINISTIC PLANNING PROBLEMS

- *Reduction of Variables for Solving Logistic Flow Problems.*

  K. Kalicharan, F. Phillipson, A. Sangers, M. De Juncker

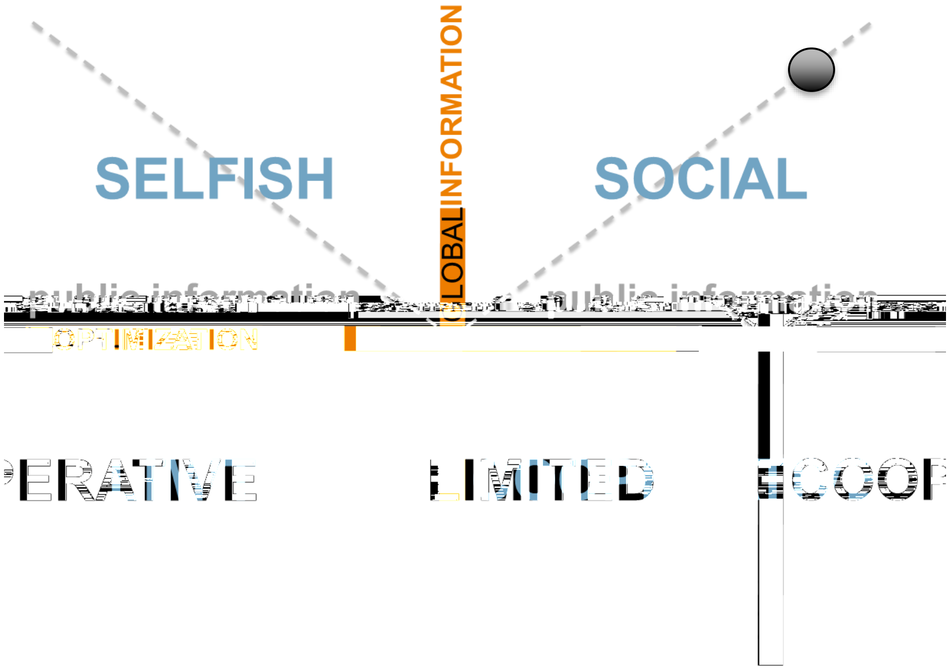
- Min-cost multi-commodity flow problem on a space-time network, [illegible]

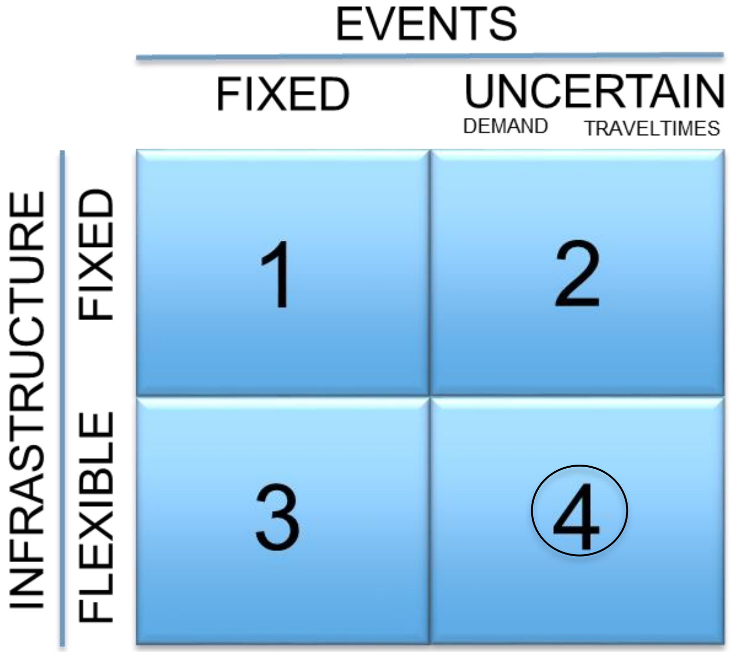
VARIABLE REDUCTIONS

- Commodity reductions:
  - Same sink/source reduction (A)
  - Disjoint time frame bookings reduction (B)
- Same vehicle type reduction (C)
- Arc reductions:
  - Source/sink location reduction (D)
  - Obsolete mode link reduction (E)
- Location reductions:
  - Minimal path reduction (F)
  - Direct connection reduction (G)

Reduction	Active	Parameter		Comp. Time	Solution
	7.12s	2600 (opt.)	A	No	K: 25
	5.86s	2600 (opt.)	A	Yes	K=25 $\rightarrow$ 20
	67.45s	3760 (opt.)	A	No	K: 50
	61.16s	3760 (opt.)	A	Yes	K=50 $\rightarrow$ 39
	61.16s	3760 (opt.)	B	No	
	43.35s	3760 (opt.)	B	Yes	
	1667.61s	3760 (opt.)	C	No	$\lvert W \rvert$: 6
	628.58s	3760 (opt.)	C	Yes	$\lvert W \rvert$=5
	183.51s	3760 (opt.)	C	Yes	$\lvert W \rvert$=4
	61.16s	3760 (opt.)	C	Yes	$\lvert W \rvert$=3
	117.61s	3760 (opt.)	D	No	
g	61.16s	3760 (opt.)	D	Yes	Sink Incomin
	64.58s	3760 (opt.)	D	Yes	Sink In/Out
	58.50s	3760 (opt.)	D	Yes	Complete
	129.98s	3760 (opt.)	F	No	
	61.16s	3760 (opt.)	F	Yes	
	> 300.00s	-	G	No	
	61.16s	3760 (opt.)	G	Yes	

PAPER 2: *DECISION MAKING IN A DYNAMIC TRANSPORTATION NETWORK: A MULTI-OBJECTIVE APPROACH*





Robust planning: define robustness and use as objective

MULTI-OBJECTIVE OPTIMIZATION OF MCMCF

- *Decision making in a Dynamic Transportation Network: a Multi-Objective Approach*

  M.R. Ortega del Vecchyo, F. Phillipson and A. Sangers

- (mathematical) Definition of alternative objectives (within the MinCostMCF-framework):
  - Robustness: the capacity of a plan to overcome delays in travel times and handling times on terminals and still be carried on as planned.
  - Flexibility: the capacity of a plan to adapt to delays in travel times and handling times on terminals when these force the plan not to be able to be carried on anymore.
  - Customer satisfaction

(1) Cost: $\sum_k \sum_{P \in P(k)} C(P)X(P)$ (and trucks $\sum_k \sum_{P \in T \subseteq P(k)} X(P)$)

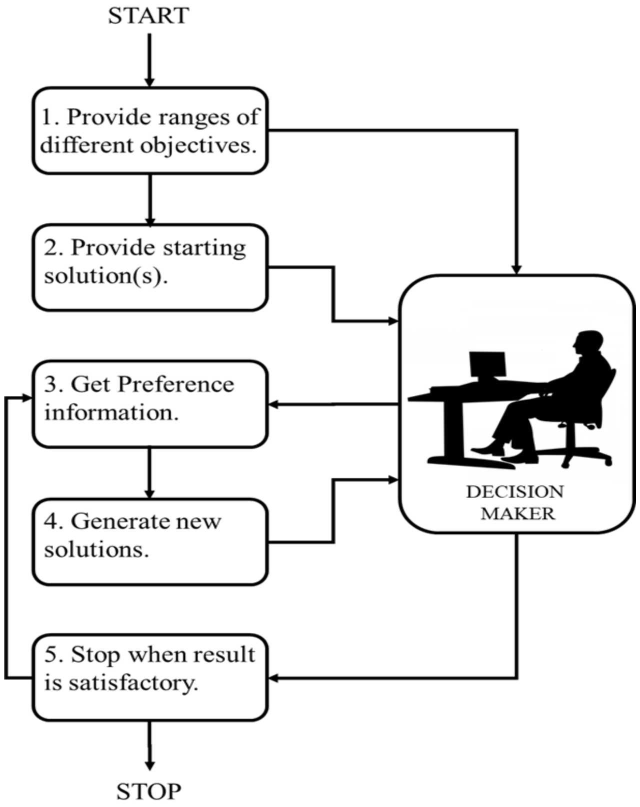
(2) Linear anti-flexibility: simple $\sum_P \iota_G(P) x_P$ (or relative $\sum_P \iota_{G \setminus F}(P) x_P$)

(3) Mean robustness: $\frac{-\lambda}{|\{e \in Pr\}|} \sum_{e \in Pr} \frac{F_e}{t_2^e - t_1^e}$ Where $\lambda = .01$

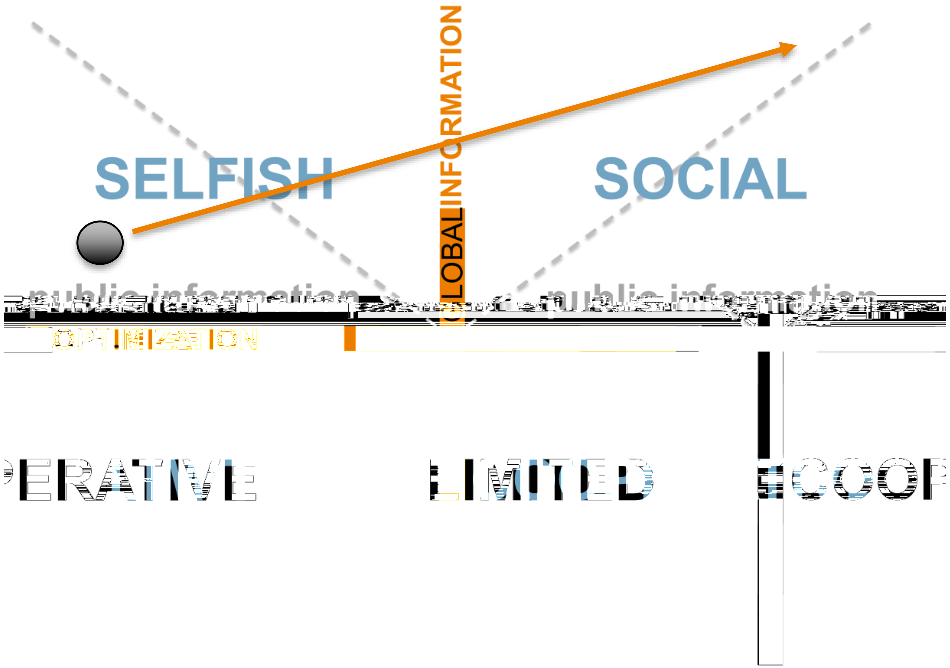
(4) Customer satisfaction: $(\sum s(o,t)w(o))^2$

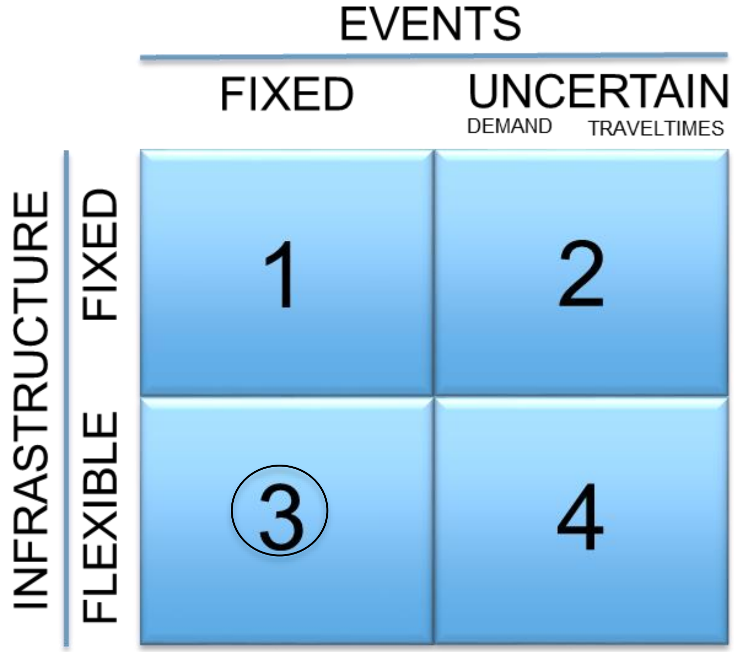
MULTI-OBJECTIVE OPTIMIZATION OF MCMCF

- Generating Pareto optimal solutions:
  - An allocation is *not* Pareto optimal if there is an alternative allocation where improvements can be made to at least one participant's well-being without reducing any other participant's well-being.
  - The Pareto frontier is the set of choices that are Pareto efficient. By restricting attention to the set of choices that are Pareto-efficient, a designer can make trade-offs within this set, rather than considering the full range of every parameter.



PAPER 3: *USER EQUILIBRIUM IN A TRANSPORTATION SPACE-TIME NETWORK*





Decentralised planning

3 FAIRLY DISTRIBUTE COSTS OF CONTAINER TRANSPORT OVER ORDERS

- *User Equilibrium in a Transportation Space-Time Network*
  L.A.M. Bruijns, F. Phillipson and A. Sangers

- Min-cost multi-commodity flow problem on a space-time network with an LSP that controls the container flows
  - Global (system) optimization and satisfy the customers simultaneously
  - Add <u>tolls</u> to orders and paths

- Looking at solutions that are System Optimal, and User Equilibrium in its tolled version.

3 FAIRLY DISTRIBUTE COSTS OF CONTAINER TRANSPORT OVER ORDERS

- Create System Optimal (SO) problem-formulation.
- Solve SO-problem → flow (f).
- Create (Non-linear) problem to find minimal path tolls (NP-β).
- Solve NP-β–problem → path tolls
- Add path tolls to SO-problem SO-β; now optimum of SO-problem = UE in that network.

- *Not really an approach to use in a Selfish environment but rather a way to distribute the 'cost of the social optimal solution' fairly.*

SUMMARY - CONCLUSIONS

- Complexity Methods for Predictive Synchromodality: incorporating models, methods and tools based on *predictive data analysis and stochastic decision making in (distributed) control environments.*

- Planning is based on data that is (more) real-time, and routes will become subject to change in real time when beneficial.

- TNO works on:
  - Fast (re-) planning methods
  - Robust planning
  - Analysis of Selfish-models

THANK YOU FOR YOUR ATTENTION

CONTACT: FRANK.PHILLIPSON@TNO.NL

Take a look:
TNO.NL/EN/TNO-INSIGHTS

TNO innovation for life

TU Delft