

**The 8th International Symposium on Dynamic Traffic Assignment (DTA 2021)**

**Analytical analysis of the effect of maximum CAV  
platoon size in mixed traffic**

Presented by

Jiazu Zhou, Feng Zhu

School of Civil and Environmental Engineering

Nanyang Technological University, Singapore

29/06/2021

# Outline

- Introduction
- Effect on capacity
- Effect on traffic stability
- Conclusions

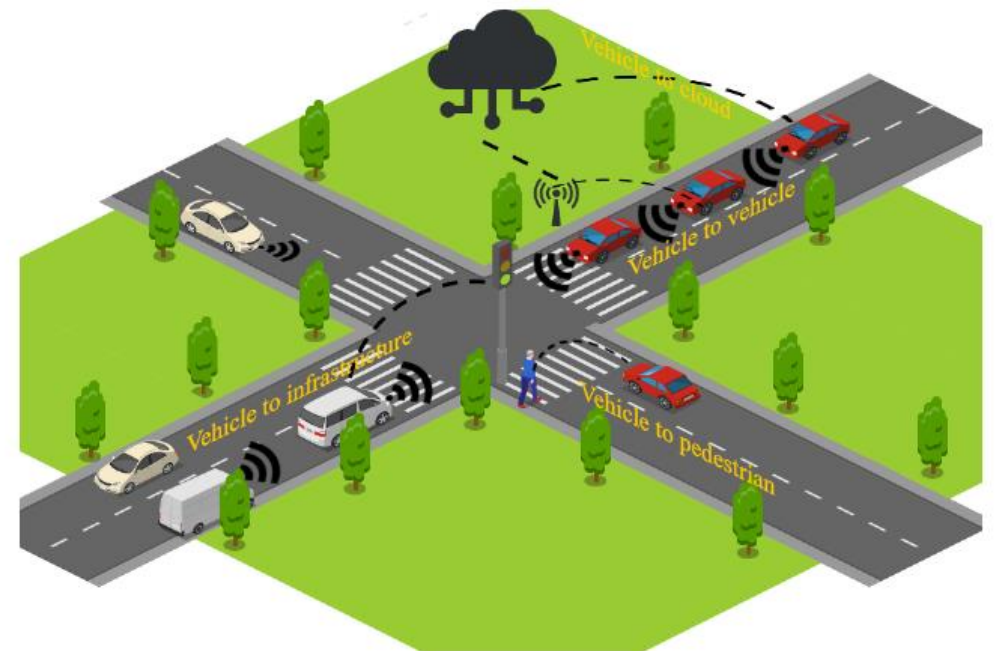
# Introduction

Connected and Automated Vehicle (CAV) platooning:

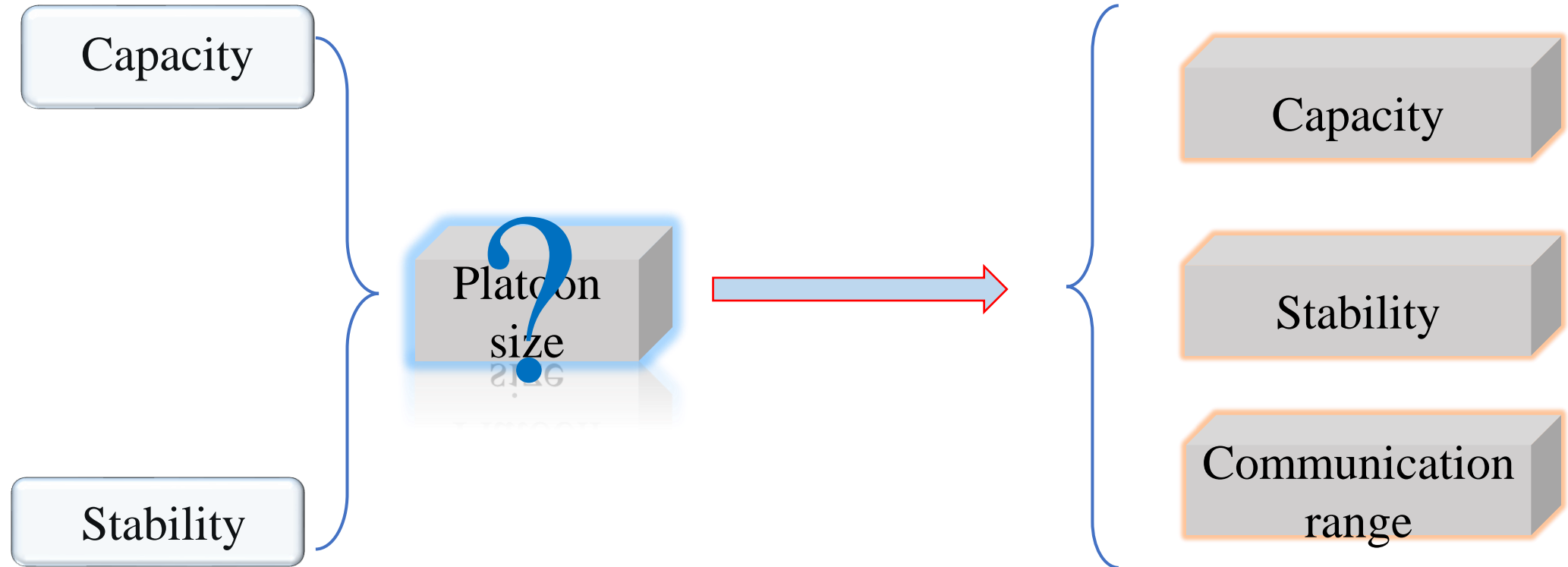
- Shorter spacing (or headway)
- Higher roadway **capacity**
- Higher **flow stability**

CAV Platoon configurations:

- Inter-platoon headway
- Intra-platoon headway
- **Maximum platoon size**



# Introduction



# Research objective

The effect of maximum platoon size on:

- capacity
- traffic stability

# Problem statement

## Basic segment of highway

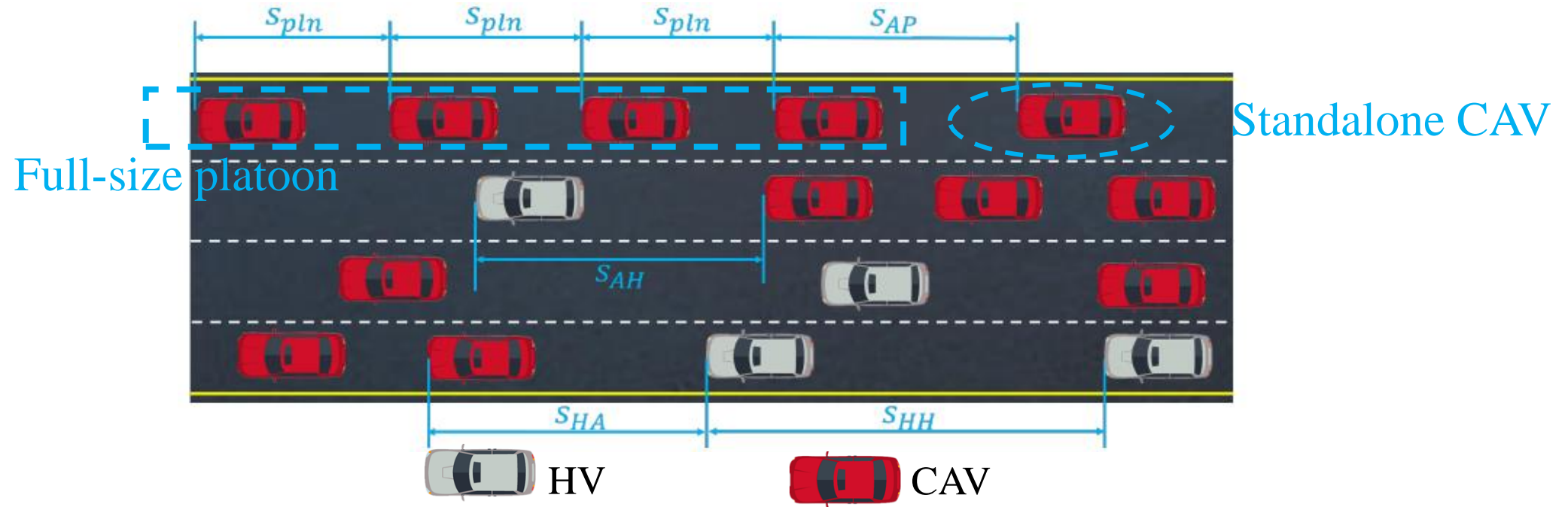


Figure 1: Five types of spacings

### Mixed traffic:

- CAV
- human-driving vehicle (HV)

### Assumption:

$$\frac{S_{pln}}{\beta_{pln}} = \frac{S_{AP}}{\beta_{AP}} = \frac{S_{AH}}{\beta_{AH}} = \frac{S_{HA}}{\beta_{HA}} = S_{HH}$$

$$\beta_{pln} < \beta_{AP} \leq \beta_{AH} \leq \beta_{HA} \leq 1 \quad 6$$

# Model parameters

Table 1. Model parameters

$N$	maximum allowable platoon size
$P_A$	CAV market penetration ( $P_A \in [0,1]$ )
$P_H$	HV market penetration ( $P_H \in [0,1]$ )
$O$	platooning intensity ( $O \in [-1,1]$ )
$s_{pln}$	intra-platoon spacing ( $km$ )
$s_{AP}$	inter-platoon spacing ( $km$ )
$s_{AH}$	spacing between a following CAV and a leading HV ( $km$ )
$s_{HA}$	spacing between a following HV and a leading CAV( $km$ )
$s_{HH}$	spacing between two HVs ( $km$ )

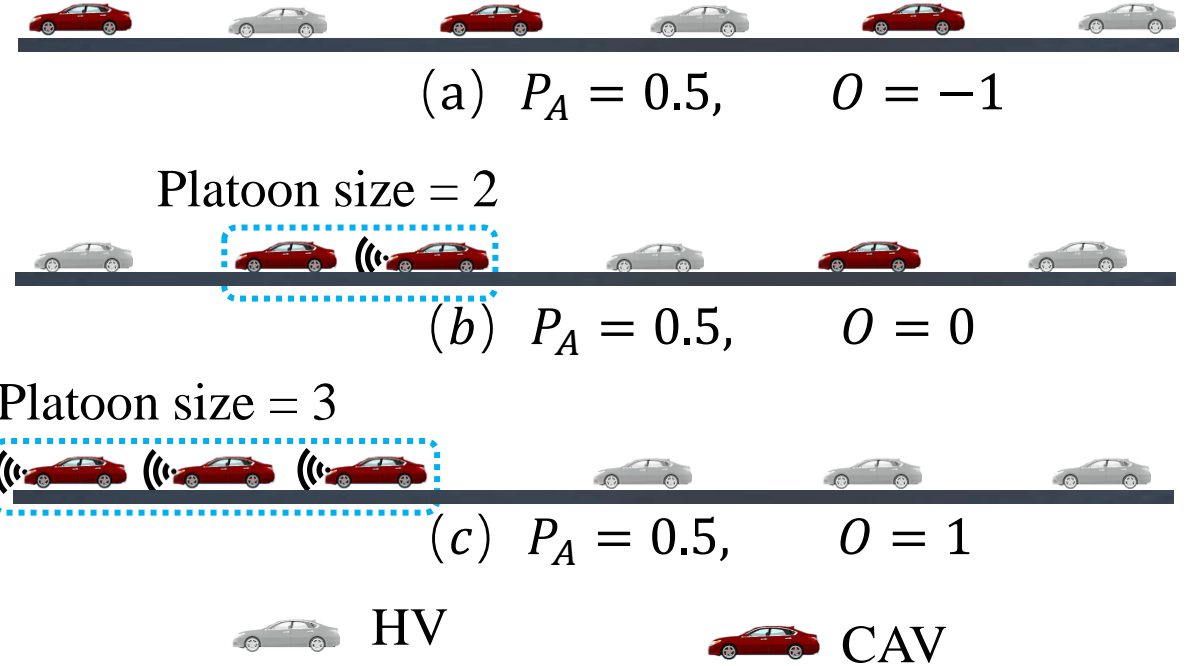


Figure 2: The illustration of  $P_A$  and  $O$

# Effect on capacity

## 1. Capacity model

Average spacing:  $\bar{s} = f(N, P_A, O, \beta_{pln}, \beta_{AP}, \beta_{AH}, \beta_{HA}, \beta_{HH}) s_{HH}$

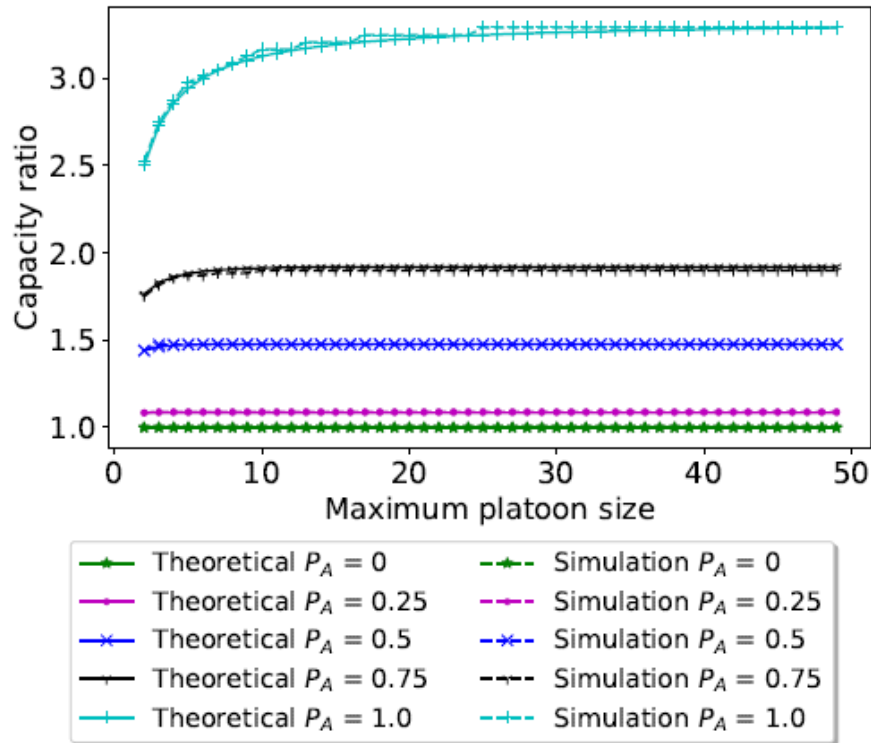
Lane capacity:  $C = \frac{1}{\bar{s}/v_f} = \frac{v_f}{f(N, P_A, O, \beta_{pln}, \beta_{AP}, \beta_{AH}, \beta_{HA}, \beta_{HH}) s_{HH}}$

Let  $C_0 = \frac{v_f}{s_{HH}}$  denotes the capacity of pure HV traffic, then the capacity is:

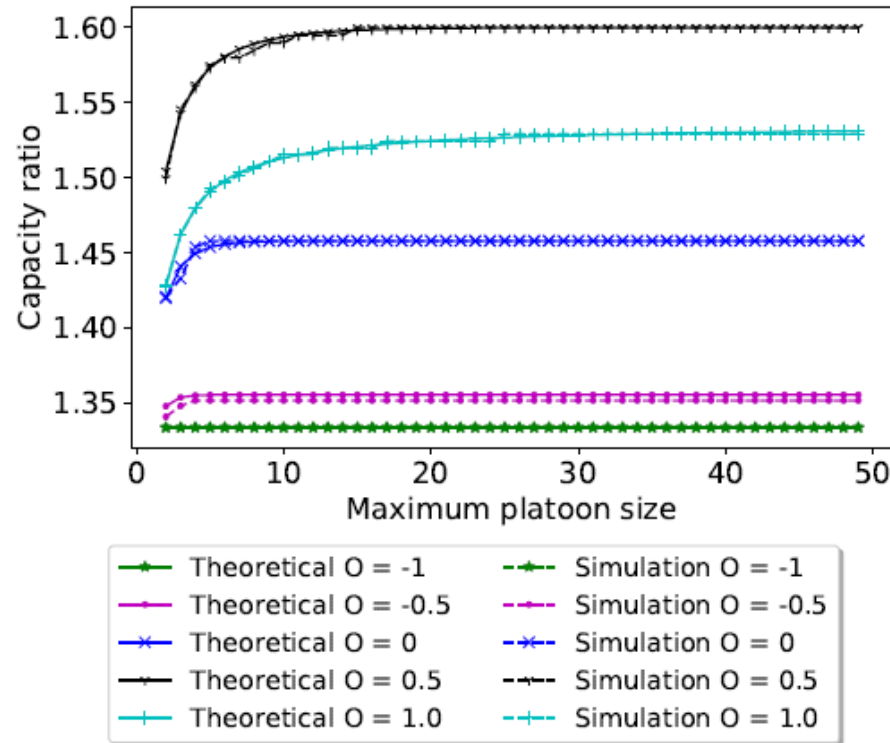
$$C = \frac{1}{f(N, P_A, O, \beta_{pln}, \beta_{AP}, \beta_{AH}, \beta_{HA}, \beta_{HH})} C_0$$



## 2. Capacity model verification



(a)  $O = 0$



(b)  $P_A = 0.5$

Figure 4: Capacity ratio vs maximum platoon size

Parameter setting:  $\beta_{pln} = \frac{0.6}{2.0}$ ;  $\beta_{AP} = \frac{1.0}{2.0}$ ;  $\beta_{AH} = \beta_{HA} = \frac{1.5}{2.0}$

1.  $N \uparrow \Rightarrow$  capacity  $\uparrow$

2.  $N \uparrow \Rightarrow$  marginal effect  $\downarrow$

(platoon size does **not necessarily** need to be set too large)

# Effect on traffic stability

## 1. Linear stability analysis (through car-following model linearization)

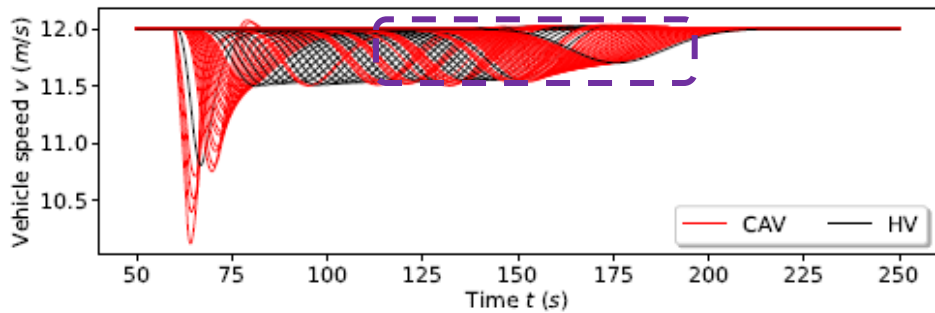
**Proposition 1.** The maximum platoon size  $N$  contributes negatively to the mixed traffic stability.

## 2. Simulation

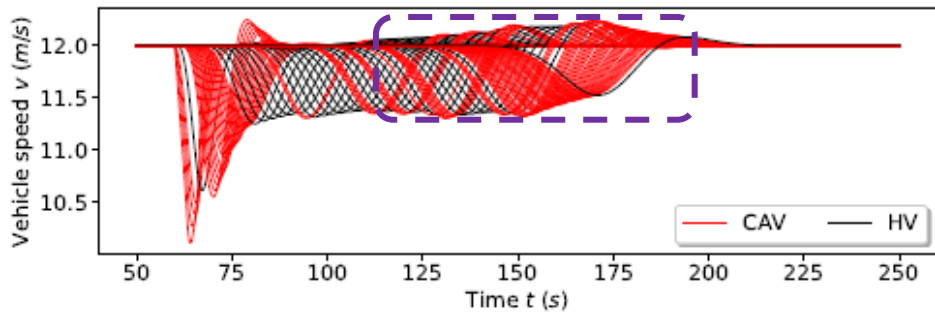
Linearization **can not** fully capture the car-following dynamics.  
The traffic that is **linearly stable** might still be **non-linearly unstable**.



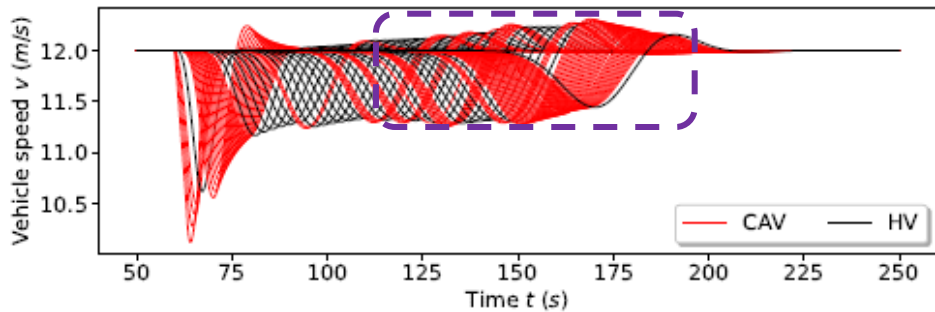
simulation



(a)  $N = 2$

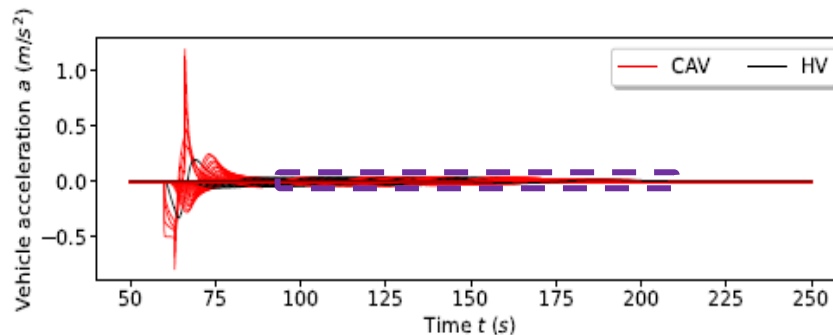


(b)  $N = 6$

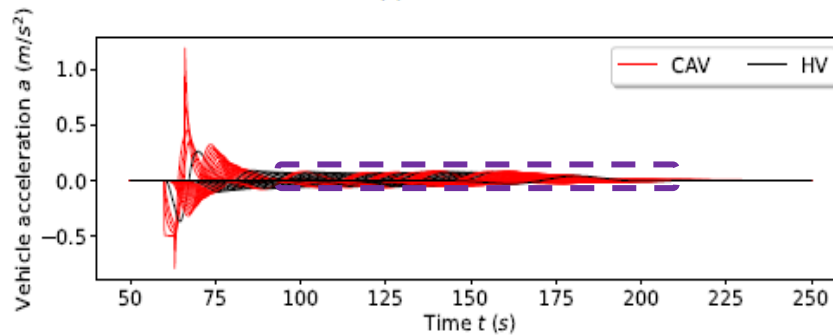


(c)  $N = 20$

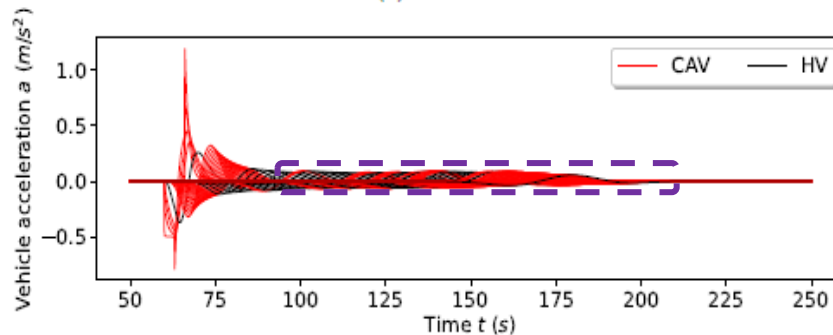
Figure 7: The speed profile



(a)  $N = 2$



(b)  $N = 6$



(c)  $N = 20$

Figure 8: The acceleration profile

Smaller  $N$  leads to more inter-platoon followings  
 Dampen wave: inter-platoon  $>$  intra-platoon

# Conclusion and future work

## Discussion

- The maximum size of CAV platoon does **not necessarily** need to be too large.
- A moderate platoon size limit is suggested considering various stakeholders.

## Contribution

- The understanding of impacts of CAV platoon size configuration
- Insights in the configuration of CAV platoon operation for future research

# Reference

- Ghiasi, A., Hussain, O., Qian, Z.S. and Li, X., 2017. A mixed traffic capacity analysis and lane management model for connected automated vehicles: A Markov chain method. *Transportation Research Part B: Methodological*, 106, pp.266-292.
- Liu, H., Kan, X., Shladover, S.E., Lu, X.Y. and Ferlis, R.E., 2018. Impact of cooperative adaptive cruise control on multilane freeway merge capacity. *Journal of Intelligent Transportation Systems*, 22(3), pp.263-275.
- Liu, H., Kan, X.D., Shladover, S.E., Lu, X.Y. and Ferlis, R.E., 2018. Modeling impacts of Cooperative Adaptive Cruise Control on mixed traffic flow in multi-lane freeway facilities. *Transportation Research Part C: Emerging Technologies*, 95, pp.261-279.
- Seraj, M., Li, J. and Qiu, Z., 2018. Modeling Microscopic Car-Following Strategy of Mixed Traffic to Identify Optimal Platoon Configurations for Multiobjective Decision-Making. *Journal of Advanced Transportation*, 2018.
- Talebpour, A. and Mahmassani, H.S., 2016. Influence of connected and autonomous vehicles on traffic flow stability and throughput. *Transportation Research Part C: Emerging Technologies*, 71, pp.143-163.
- Van Arem, B., Van Driel, C.J. and Visser, R., 2006. The impact of cooperative adaptive cruise control on traffic-flow characteristics. *IEEE Transactions on Intelligent Transportation Systems*, 7(4), pp.429-436.
- Xiao, L., Wang, M., Schakel, W. and van Arem, B., 2018. Unravelling effects of cooperative adaptive cruise control deactivation on traffic flow characteristics at merging bottlenecks. *Transportation Research Part C: Emerging Technologies*, 96, pp.380-397.
- Zhou, J. and Zhu, F., Analytical analysis of the effect of maximum platoon size of connected and automated vehicles. *Transportation Research Part C: Emerging Technologies*, 122, p.102882.

Comments and suggestions ?  
Thank you!