Optimal Path Planning using Equilateral Spaces Oriented Visibility Graph Method

Nor Badariyah Abdul Latip, Rosli Omar, Sanjoy Kumar Debnath
Universiti Tun Hussein Onn Malaysia, Faculty of Electrical and Electronic Engineering, 86400 Parit Raja, Batu Pahat, Johor, Malaysia

ABSTRACT

Path planning has been an important aspect in the development of autonomous cars in which path planning is used to find a collision-free path for the car to traverse from a starting point Sp to a target point Tp. The main criteria for a good path planning algorithm include the capability of producing the shortest path with a low computation time. Low computation time makes the autonomous car able to re-plan a new collision-free path to avoid accident. However, the main problem with most path planning methods is their computation time increases as the number of obstacles in the environment increases. In this paper, an algorithm based on visibility graph (VG) is proposed. In the proposed algorithm, which is called Equilateral Space Oriented Visibility Graph (ESOVG), the number of obstacles considered for path planning is reduced by introducing a space in which the obstacles lie. This means the obstacles located outside the space are ignored for path planning. From simulation, the proposed algorithm has an improvement rate of up to 90% when compared to VG. This makes the algorithm is suitable to be applied in real-time and will greatly accelerate the development of autonomous cars in the near future.

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Corresponding Author:
Rosli Omar,
Faculty of Electrical & Electronic Engineering,
Universiti Tun Hussein Onn Malaysia,
86400 Parit Raja, Batu Pahat, Johor, Malaysia.
Email: roslio@uthm.edu.my

1. INTRODUCTION

Path planning has been an emerging trend research nowadays to cater the needs of autonomous systems. Without path planning, autonomous cars could not be materialized. Currently, there are many path planning algorithms that have been developed based on methods such as Voronoi diagram (VD) [1], [2], cell decomposition (CD) [3], [4], genetic algorithm (GA) [5], [6] and visibility graph (VG), to name a few. A path planning algorithm’s performance is normally measured based on three criteria which include the computation time, path optimality and completeness.

Basically, the main constraint that affects the computation time of path planning is the number of obstacles contained in a configuration space (C-space). In C-space size of the autonomous car is reduced to a point and the size of obstacle is enlarge based on the size of autonomous car [7]. The higher the number of obstacles in C-space, the higher the computation time to find a collision-free path.

An optimal path can be defined as the shortest path generated by a path planning algorithm among all the produced path commencing from the starting point Sp to the end point Tp [2], [8-11]. A path planning algorithm holds the completeness criterion if it is able to produce a path if one exists.

There are several types of path planning such as combinatorial and bio-inspired. Each of them has their benefits and drawbacks in satisfying the above-mentioned criteria.
VG is a complete algorithm and capable of producing a path with the shortest distance but its drawback is the computation time increases when the number of obstacles in C-spaces increases [9], [10], [12]. VD, on the other hand, uses equidistant techniques to discover a path for which an optimal path cannot be accomplished although it has relatively lower computation time and the algorithm is complete [2], [13].

CD divides the C-spaces into cells which are discrete and non-overlapping. A path is then produced through a cell that is not occupied by the obstacle. The drawback of this method is that it cannot produce optimal path albeit it has a lower computation time. CD is complete where it finds a path if one exists.

The bio-inspired type gets motivation from nature. An application of operators is used in the Genetic algorithm (GA) to emulate natural selection process. The disadvantage of GA is that there are possibilities of not finding the solution in narrow environments as the local minima conditions may occur. Conversely, GA works in parallel and thus, uses less computation time. It is meta-heuristics and hence, does not guarantee the shortest distance [5], [6], [14].

As VG is capable of producing the shortest path and complete, in this paper, an algorithm based on VG is proposed and the simulation is performed using MATLAB to evaluate the performance of the proposed algorithm.

2. PATH PLANNING ALGORITHM

The proposed algorithm, called Equilateral Space Oriented Visibility Graph (ESOVG), is depicted in Figure 1. The idea of the algorithm is to reduce the number of obstacles used when planning a path, which will in turn, lessen the computation time.

The algorithm starts with creating a base line, which connects the starting point Sp and target point Tp. The opening angle ρ is then set to nominal value of 20°. After that, a mid-point between Sp and Tp is identified. This is followed by creating a mid-line which is perpendicular to the base line and intersecting the mid-point. Then, a pair of imaginary lines, which emerge from Sp towards the mid-line with an opening angle of ρ are created. Similarly, another pair of imaginary lines emerging from Tp towards the mid-line are drawn. Both pairs of lines should intersect the points denoted by C₁ and C₂. The equilateral space, shown in darker colour, which is formed by four imaginary lines is illustrated in Figure 2.

| Algorithm: ESOVG |
|------------------|
| 1: Create a base line connecting starting point Sp and target point Tp |
| 2: Set the nominal opening angle ρ to 20° |
| 3: Identify a mid-point on the base line between Sp and Tp |
| 4: Create a mid-line passing through the mid-point and perpendicular to the base line |
| 5: From each Sp and Tp, create a pair of imaginary lines with an opening angle of ρ towards the mid-line |
| 6: Create an equilateral space from the enclosed area by the four imaginary lines drawn in step 5 |
| 7: Identify the obstacles, O located in the equilateral space |
| 8: Identify nodes list of the obstacle in step 7 |
| 9: Construct a cost matrix based on the nodes list |
| 10: Find the shortest path from Sp to Tp using Dijkstra’s algorithm |
| 11: If no path is found within the equilateral space, go to step 2 and increase ρ by 5°. |

Figure 1. The proposed algorithm

Figure 2. The equilateral space
In this algorithm, the size of the generated equilateral space depends on the opening angle \( \rho \). The nominal angle is set at 20\(^\circ\) so that the path planning can be performed with a low computation time as the number of obstacles contained in the area is small. However, if a path is not found in the space, the angle is then increased by 5\(^\circ\) until one is found.

Figures 3(a)-Figure 3(d) show the simulation of ESOVG using \( \rho = 20^\circ, 30^\circ, 40^\circ \) and \( 50^\circ \), respectively. The figures show 100 obstacles present in the C-spaces but only a few obstacles (shown in green) are being considered by ESOVG for path planning as they are fully or partially contained in the equilateral space (enclosed by the solid lines). On the other hand, the obstacles shown in white are ignored as they are totally outside the space. Notice that the smaller the opening angle \( \rho \), the lesser the number of obstacles are taken into account. The computation time and path length for each \( \rho \) are shown in Table 1.

![Simulation of path planning using ESOVG](image)

**Table 1. Computation time and path length using different values of \( \rho \)**

| \( \rho \)  | Computation time (s) | Path length (unit) |
|------------|----------------------|--------------------|
| 20\(^\circ\) | 0.4389               | 645.675            |
| 30\(^\circ\) | 0.7145               | 645.675            |
| 40\(^\circ\) | 1.5478               | 645.675            |
| 50\(^\circ\) | 2.3856               | 645.675            |

The piecewise linear segments shown in dashed line are the resulting path of ESOVG. From Table 1, it is observed that as \( \rho \) is enlarged, the computation time increases. This is due to the fact that the number of obstacles contained in the equilateral space is increased by enlarging \( \rho \). However, the path lengths are identical with different \( \rho \). Thus, it is important to decide the value of \( \rho \) that can produce an optimal path while minimizing the computation time.

3. **SIMULATION RESULTS**

The efficiency of the algorithm can be observed through a simulation with different number of obstacles, i.e. between 15 and 150. These numbers of obstacles represent different density of the obstacles in a C-space. To see the effect of the opening angle \( \rho \), three different values are applied which are 20\(^\circ\), 30\(^\circ\) and
40°. Table 2 shows the comparison of computation time to search the collision-free paths by ESOVG with different number of obstacles and opening angles ρ. When ρ is 20° and with 15 obstacles in the search space, the computation time to find a path is 0.0679s. As ρ is enlarged to 30° and 40°, the computation times are 0.0955s and 0.1251s, respectively.

When the number of obstacles is increased to 120, the computation time at ρ=20° is 0.6156s. With the same number of obstacles, at ρ=30° and ρ=40°, the computation times are 1.0248s and 2.1233s respectively. With the number of obstacles of 150 in the C-space, at ρ = 20°, 30° and 40°, the computation times are 1.0334s, 1.6662s and 3.0275s, respectively. The simulation result shows that when ρ is small, which results in small equilateral space and a low number of obstacles, the computation time is lower. The trend of the computation times of the simulation is depicted in Figure 4.

The performance of the proposed algorithm is evaluated by comparing it with the conventional VG method. Table 3 shows the comparison of computation time and path length between the conventional VG and ESOVG with ρ=20°.

| Number of obstacles | Computation time(s) at ρ=20° | Computation time(s) at ρ=30° | Computation time(s) at ρ=40° |
|---------------------|------------------------------|------------------------------|------------------------------|
| 15                  | 0.0679                       | 0.0955                       | 0.1251                       |
| 30                  | 0.1311                       | 0.1808                       | 0.2753                       |
| 45                  | 0.1599                       | 0.1992                       | 0.3683                       |
| 60                  | 0.2439                       | 0.2903                       | 0.5371                       |
| 75                  | 0.3541                       | 0.4602                       | 0.8798                       |
| 90                  | 0.3880                       | 0.5607                       | 1.2418                       |
| 105                 | 0.4545                       | 0.7324                       | 1.5761                       |
| 120                 | 0.6156                       | 1.0248                       | 2.1233                       |
| 150                 | 1.0334                       | 1.6662                       | 3.0275                       |

Figure 4. Simulation results of ESOVG with different ρ values and different numbers of obstacles

| No of obstacles | Conventional VG | ESOVG with ρ=20° |
|----------------|----------------|------------------|
|                | Computation time (s) | Path length (unit) | Computation time (s) | Path length (unit) | Improvement rate (%) |
| 15             | 0.1862 | 520.1343 | 0.0679 | 520.1343 | 63.5 |
| 30             | 0.6523 | 520.1342 | 0.1311 | 520.1343 | 79.9 |
| 45             | 1.4568 | 627.4492 | 0.1599 | 627.4492 | 89.0 |
| 60             | 2.2357 | 631.0024 | 0.2439 | 631.0024 | 89.0 |
| 75             | 3.2087 | 645.6750 | 0.3541 | 645.6750 | 89.0 |
| 90             | 4.4143 | 645.6750 | 0.3880 | 645.6750 | 91.2 |
| 105            | 6.0465 | 645.6750 | 0.4545 | 645.6750 | 92.5 |
| 120            | 7.3873 | 750.2258 | 0.6156 | 750.2258 | 92.0 |
| 150            | 11.8671 | 910.8723 | 1.0334 | 910.8723 | 91.3 |

Table 2. Comparison of computation times with different values of ρ and obstacles

Table 3. Performance comparison between conventional VG and ESOVG
When the number of obstacles is 15, the computation time for finding a path by conventional VG is 0.1862s, and by ESOVG is 0.0679s. ESOVG improves the computation time by up to 63.5%. When the number of the obstacle is increased to 75, the computation time of conventional VG is 3.2087s while the ESOVG’s is 0.3541s, which reduces the VG computation time by 89%. With 150 obstacles in the environment, the computation time by conventional VG and ESOVG are 11.8671s and 1.0334s respectively. The improvement recorded by ESOVG is 91.3%.

Figure 5 clearly shows the trends of computation times of conventional VG and ESOVG. The trend indicates that when the number of obstacles escalates, the computation time of conventional VG increases exponentially, whereas ESOVG has computation time that rises almost linearly.

In terms of path length, from Table 3, it can be seen that both VG and ESOVG produce path with identical lengths. This proves that while ESOVG reduces the computation time, it maintains the optimality of the resulting path in terms of length.

4. CONCLUSION

Equilateral Spaces Oriented Visibility Graph (ESOVG) algorithm has been proposed in this paper to overcome a high computation time in conventional VG. ESOVG creates an equilateral space using four imaginary lines to reduce the considered number of obstacles when planning a collision-free path. In ESOVG, the size of the equilateral space is determined by the opening angle $\rho$. The nominal value of $\rho$ is set to 20º and if a collision-free path could not be found in the space, it will be increased gradually until a path is found in the space. ESOVG has been compared with the conventional VG in terms of computation time and path length. It was found that ESOVG was able to improve the computation time drastically in comparison with the conventional VG while the optimality of the path length was maintained. In the future ESOVG could be tested in a dynamic environment which has moving and pop-up obstacles. If ESOVG were success in dynamic environment, it could be applied in autonomous car, in which a lower computation time is necessary in order to be applied in real time.

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BIOGRAPHIES OF AUTHORS

Nor Badariyah Abdul Latip, received her bachelor in Electronic Engineering from Universiti Tun Hussein Onn Malaysia (UTHM) in 2015. Her research interests are in robotic path planning, control system and medical electronic. Upon graduation she pursues his master in Electrical Engineering in UTHM. She is currently a Master degree student at UTHM.

Roslil Omar is a senior lecturer at Faculty of Electrical & Electronic Engineering, Universiti Tun Hussein Onn Malaysia. He received his PhD in engineering from University of Leicester, United Kingdom in 2012. His research interests are in robotic engineering, autonomous system and system identification.

Sanjoy Kumar Debnath is a 2nd-year PhD student in the Department of Mechatronic and Robotic engineering, Faculty of Electrical & Electronic Engineering in the Universiti Tun Hussein Onn Malaysia (UTHM). He received his Masters of Engineering from Universiti Teknologi Malaysia in 2014 and Bachelor of Engineering Degree from the Presidency University Bangladesh in 2008. He joined a research on “Optimal Energy Efficient Path Planning for an Unmanned Air Vehicle (UAV) in Obstacle-Rich Environment” in 2015 at UTHM with research Grant under the Office for Research, Innovation, Commercialization, and Consultancy Management (ORICC).