Efficient Route Planning SS 2011

Lecture 5, Friday June 10th, 2011 (Web application, Google Maps API, ...)

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Overview of this lecture

- Feedback from the exercises
 - Your experiences & your experimental results
 - Information about the final **exam** on Monday, August 15
- A route planner web application
 - Your next exercise:
 - build a web application, based on Google Maps
 - where you can specify source and target location
 - and the application will show the shortest path
 - computed by a server running your algorithms
 - To this end, we will learn something today about
 - Google Maps API, HTML, DOM, CSS, JavaScript, jQuery, AJAX, JSON, JSONP, sockets, ...

Feedback for Exercise Sheet 2 (Landmarks)

Summary / excerpts

- Less work than exercise sheet 1
- A lot of work spent on refactoring code from ES1
- Proofs were ok
- More feedback on the code would be nice [ok]
- Master solutions would be nice [done]
- Problems with Ant + JUnit [solved by now]
- Clear guidelines missing on how to deal with: isolated nodes, multiple connected components, ...

Summary / excerpts

- Took quite a lot of time, some say too much for 1 week
- Parts of the algorithm's description too vague
- Complete and correct solution to exercise sheet 1 was an essential prerequisite
- Too much programming of trivial things, costs a lot of time but little learning effect

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See the table on the Wiki

- Many results still missing, please put them there!
- The results which are there are quite conclusive:
 - Arc flags much faster then Dijkstra and the two A* heuristics we have seen so far
 - For Saarland and 1000 regions, up to **100** times faster!
 - But half an hour of precomputation
 - Let's look at some typical search spaces ...

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Final exam

Some information

- Will take place on Monday, August 15, 2011
- It will most probably be a written exam
 - $2 2 \frac{1}{2}$ hours, starting at 2:00 pm, here in HS 026
 - 4 5 tasks, 30 minutes each
- Unless only \leq 10 of you want to take the exam
 - then I will make it an oral exam

Computing the shortest path ...

- and not only its cost
 - Can be easily done along with Dijkstra's algorithm
 - For each node also maintain a parent pointer
 - Whenever a node u gets a new tentative distance
 - from a node v via an arc (u, v)
 - set the parent pointer of u to v
 - For costs > 0, these parent pointers can never form a cycle
 - Hence they form a tree (the shortest path tree in the end)
 - The shortest path to any settled node is obtained by following the parent pointers to the source

Computing the shortest paths ...

and not only its cost, here is an example:

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References

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 - <u>http://code.google.com/apis/maps/documentation/javascript/</u>
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