

Aircraft delivery vehicle with fuzzy time window for improving search algorithm

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Abstract. Drones are increasingly used in logistics delivery due to their low cost, high-speed and straight-line flight. Considering the small cargo capacity, limited endurance and other factors, this paper optimized the pickup and delivery vehicle routing problem with time windows in the mode of “truck+drone”. A mixed integer programming model with the objective of minimizing transportation cost was proposed and an improved adaptive large neighborhood search algorithm is designed to solve the problem. In this algorithm, the performance of the algorithm is improved by designing various efficient destroy operators and repair operators based on the characteristics of the model and introducing a simulated annealing strategy to avoid falling into local optimum solutions. The effectiveness of the model and the algorithm is verified through the numerical experiments, and the impact of the “truck+drone” on the route cost is analyzed, the result of this study provides a decision basis for the route planning of “truck+drone” mode delivery.

Keywords: adaptive large neighborhood search algorithm; pick-up and delivery problem with time window; vehicle routing

1. Introduction

With the rapid development of e-commerce, the demand for logistics continues to rise, and many logistics companies begin to pay attention to the efficiency and economy of distribution (Chen 2008, Chen 2007, Hsieh 2005, Chen 2010, Zhao *et al.* 2023). Due to the advantages of low cost, fast speed, and straight-line driving, drones have attracted the attention of many companies in the last mile delivery. Many companies such as Amazon, Google, and DHL have carried out practical experiments, and are gradually building unmanned aerial vehicles. Man-machine distribution system (Alimoradzadeh *et al.* 2023, Jafari *et al.* 2023, Khosravikhor *et al.* 2023, Al-Jaafari *et al.* 2023, Shih 2012, Shih 2023). However, drones have the disadvantages of small cargo capacity, short cruising range, and susceptibility to interference, so they cannot meet the needs of modern logistics when used alone. Using the joint distribution of trucks and UAVs, taking advantage of the advantages of UAVs, reducing the number of distribution trucks, can reduce transportation costs and improve distribution efficiency (Lee 2012, Lee 2023, Lin 2009, Lin 2013,

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Liu 2013, Liu 2023, Akbari *et al.* 2023, Aksoylu *et al.* 2023).

It is an excellent semi-active damping device and can be widely used in transportation and other fields, such as automobile suspension systems. And it is beneficial to improve the comfort and running quality of the vehicle (Chandrasekaran *et al.* 2023, Chen *et al.* 2023, Hsu 2013, Kuan 2012, Chen 2013, Cheng 2023). As a critical device in vibration damping systems, the engineering design of an MR damper directly impacts its performance index, and a reasonable simulation can get the best design scheme in the shortest time with the least manpower and material resources (Liu *et al.* 2022). Wang built a vehicle routing problem model for UAVs, and verified that the delivery time of the joint delivery of trucks and UAVs is less than that of trucks alone even in the worst case (Chiou 2023, Fard *et al.* 2023, Gholizadeh *et al.* 2023, Ayough *et al.* 2023, Bai *et al.* 2023, Kuo 2010). Scramento *et al.* for VRP-D An adaptive large neighborhood search algorithm is proposed to solve the model. Meng Shanshan *et al.* considered the multi-truck-UAV mixed delivery problem where the UAV can carry multiple packages at a time, and proposed a two-stage collaborative optimization algorithm to minimize the cost (Abad *et al.* 2023, Zou 2023, Banh *et al.* 2023, Behshad *et al.* 2023, Biao *et al.* 2023, Bounouara *et al.* 2023).

and delivery vehicle routing problem with time window (Pickup and Delivery Problem with Time Windows, PDPTW) not only has a wide range of applications in logistics distribution, but also has been a hot spot in academic research, Baldacci *et al.* solve it by combining multiple exact algorithms such as integer programming, dual theory and column generation (Hsiao 2005, Tsai 2008, Tsai 2023, Yeh 2013, Zaoui *et al.* 2023, Zhan *et al.* 2023). Bent uses a two-stage algorithm to solve PDPTW, the first stage uses a simulated annealing algorithm to reduce the number of vehicles, and the second stage uses a large neighborhood search algorithm to minimize the path cost. Ropke proposed to solve PDPTW based on the large neighborhood search algorithm Adaptive Large Neighborhood Search Algorithm (Adaptive Large Neighborhood Search, ALNS), the results show that ALNS has a good effect on solving large-scale problems. Goeke proposed an improved tabu search algorithm to solve the electric vehicle pick-up and delivery problem with a time window. Leng Longlong *et al.* established a low-carbon location-routing problem model for simultaneous pickup and delivery with the goal of carbon emissions, and used the quantum hyperheuristic algorithm to solve the model. Ren Teng *et al.* analyzed the transportation department's service for e-commerce orders while picking up and delivering intra-city orders, and constructed a path optimization that minimizes the total expenditure of individual customers, e-commerce enterprise customers and the transportation department. Mathematical model, and design an improved genetic algorithm to solve it (Cánovas-González *et al.* 2023, Hong *et al.* 2023, Chen 2014, Chiang 2010, 2011, Zhang *et al.* 2023, Chen 2009).

In the previous literature, there has been no research on PDPTW under the “truck+drone” mode. As the commercial value of drones continues to be tapped, the demand for intra-city delivery, “fresh food home” and takeaways, etc. Continuously rising, considering the model of truck+UAV, optimizing PDPTW can enrich the logistics distribution model and expand the business scenario of UAV. Therefore, this article focuses on the pickup and delivery with time window under the “truck+UAV” mode Vehicle routing problem (Pickup and Delivery Problem with Time Windows and Drone, PDPTW-D) was studied, and a PDPTW-D mixed integer programming model was established to minimize the number of vehicles and routing costs, the ALNS algorithm was proposed to solve the problem. In this algorithm, a variety of efficient damage operators and repair operators based on the characteristics of the model are proposed, and simulated annealing acceptance criteria are introduced to avoid falling into local optimal solutions to improve the performance of the algorithm. The effectiveness of the algorithm is verified by

testing examples of different scales, and the results show that the joint transportation mode of trucks and UAVs can save a lot of route costs.

2. System description

The research problem of this paper can be described as: there is only one distribution center in the logistics network, and the distribution center has an unlimited number of trucks of the same type and drone. The truck departs from the distribution center, and each truck carries a drone. The vehicle load must not exceed its maximum capacity. The truck first picks up the goods at the pick-up point, and then the truck or drone delivers the goods to the corresponding delivery point. During the delivery process, both the truck and the drone keep moving at a constant speed. The drone starts from the truck, and can only deliver to the delivery point where the cargo capacity and battery life meet the constraints, and then merge with the truck. When the drone is delivering, the truck goes to the next customer point to complete the pick-up and delivery needs. The battery will be replaced immediately after the drone meets the truck to ensure the endurance of the next drone flight. Each customer point can only be visited once by a truck or drone. Vehicle access must meet the requirements of the customer time window. If it arrives earlier than the start time of the customer time window, it needs to wait, and if it arrives later than the end time of the time window, it cannot visit.

Symbols and parameters

- $P = \{1, 2, \dots, n\}$ collection of pick-up points
 - $D = \{n+1, \dots, 2n\}$ set of delivery points
 - $K = \{1, 2, \dots, k\}$ set of trucks
 - M : infinite number
 - Q : The maximum cargo capacity of the truck
 - e : the maximum battery life of the drone d_{ij} : the driving distance of the vehicle from i to j c : the distance cost coefficient of the drone delivery e_i, l_i : time window range of client i
 - L : The time it takes to launch the drone
 - R : the time it takes to recover the drone
 - w_{xya} : 0-1 variable, 1 when truck passes arc (i, j)
 - y_{ijk} : 0-1 variable, 1 when drone passes arc (i, j)
 - s_j : the truck is at customer j service hours
 - t_{ik} : truck arrives at customer point i time
 - td_{ik} : the time when the drone arrives at customer point i
- When 0 is the starting point, $2n+1$ is the end point, D' is the set of customer points that the drone can visit in the delivery point, and P' is the set of corresponding pick-up points. where $N = P \cup D, V = N \cup \{0, 2n+1\}, D' \subseteq D, P' \subseteq P$.

PDPTW-D Model

The constructed PDPTW-D model is as follows

$$\left(\sum_{k \in K} \sum_{j \in P} x_{0jk}, \sum_{k \in K} \sum_{i \in V} \sum_{j \in V} x_{ijk} d_{ij} + \sum_{k \in K} \sum_{i \in V} \sum_{j \in V} c d_{ij} y_{ijk} \right) \tag{1}$$

min

$$\sum_{k \in K} \sum_{j \in N} x_{ijk} = 1, \forall i \in P \tag{2}$$

$$\text{st } \sum_{j \in N} x_{ijk} = \sum_{j \in N} x_{j,n+i,k}, \forall i \in P \setminus P', \forall k \in K \quad (3)$$

$$\sum_{j \in N} x_{ijk} - \sum_{j \in N} x_{j,n+i,k} - \sum_{j \in N} y_{j,n+i,k}, \forall k \in K, \forall i \in P' \quad (4)$$

$$\sum_{j \in P} x_{0jk} = 1, \forall k \in K \quad (5)$$

$$\sum_{i \in D} x_{i,2n+1,k} = 1, \forall k \in K \quad (6)$$

$$x_{0,2n+1,k} = 0, \forall k \in K \quad (7)$$

$$\sum_{i \in V} x_{iik} = 0, \forall k \in K \quad (8)$$

$$\sum_{i \in V} y_{iik} = 0, \forall j \in N, \forall k \in K \quad (9)$$

$$\sum_{i \in V \setminus \{2n+1\}} x_{ijk} - \sum_{m \in V \setminus \{0\}} x_{jmk} = 0, \forall j \in N, \forall k \in K \quad (10)$$

$$\sum_{j \in N} y_{ijk} \leq 1, \forall k \in K, \forall i \in N, \quad (11)$$

$$\sum_{j \in N} y_{jik} \leq 1, \forall k \in K, \forall i \in N \quad (12)$$

$$\sum_{i \in N} y_{ijk} = \sum_{i \in N} y_{jik}, \forall k \in K, \forall j \in D' \quad (13)$$

$$y_{ijk} + y_{jmk} \leq x_{imk} + 1, \forall k \in K, \forall i \in N, \forall j \in D, \forall m \in N \quad (14)$$

$$t_{ik} \leq t_{n+i,k}, \forall k \in K, \forall i \in P \quad (15)$$

$$t_{ik} \leq td_{n+i,k}, \forall k \in K, \forall i \in P' \quad (16)$$

$$td_{ik} \geq t_{ik} - M(1 - \sum_{i \in D'} y_{ijk}), \forall k \in K, \forall i \in N \quad (17)$$

$$td_{ik} \leq t_{ik} + M(1 - \sum_{j \in D'} y_{jik}), \forall k \in K, \forall i \in N \quad (18)$$

$$td_{mk} \geq t_{mk} - M(1 - \sum_{j \in D'} y_{jmk}), \forall k \in K, \forall m \in N \quad (19)$$

$$td_{mk} \leq t_{mk} + M(1 - \sum_{j \in D'} y_{jmk}), \forall k \in K, \forall m \in N \quad (20)$$

$$L y_{ijk} + R y_{jmk} + t_{ik} + t_{im}^T + S_i \leq t_{mk} + M(1 - x_{imk}), \forall k \in K, \forall j \in D', \forall i \in N, \forall m \in N \quad (21)$$

$$\begin{aligned} td_{jk} &\geq td_{ik} + cd_{ij} + L - M(1 - y_{ijk}), \forall k \in K, \forall j \in D', \forall i \in N, \forall m \in N \\ td_{jk} &+ cd_{jm} + S_j + R - M(1 - y_{jmk}) \leq td_{mk}, \forall k \in K, \forall j \in D', \forall m \in N \\ e_i &\leq t_{ik} \leq l_i, \forall k \in K, \forall i \in V \\ e_i &\leq td_{ik} \leq l_i, \forall k \in K, \forall i \in D' \end{aligned} \quad (25)$$

$$\sum_{j \in N} (\sum_{m \in V \setminus \{0\}} p_j x_{jmk} + \sum_{m \in V \setminus \{0\}} p_j y_{jmk}) \leq Q, \forall k \in K \quad (26)$$

$$td_{mk} - td_{ik} \leq e + M(2 - y_{ijk} - y_{jmk}), \forall k \in K, \forall i \in N, \forall j \in D' \quad (27)$$

The objective function (1) is to minimize the path cost, that is, to minimize the truck path cost and the UAV path cost. Constraint (2) means that each pick-up point is access. Constraint (3) means that for delivery points whose demand can only be satisfied by trucks, when the pick-up point is visited, the delivery point is visited by trucks. Constraint (4) means that for a delivery point whose demand is satisfied by drone delivery, when the pick-up point is visited, the delivery point is visited by a truck or a drone. Constraint (5) states that each truck must leave the distribution center. Constraint (6) states that each truck must return to the distribution center. Constraint (7) states that trucks are not accepted for transport only between distribution centers. Constraints (8)-(9) are removed from loops. Constraint (10) ensures path continuity. Constraints (11)-(12) state that each truck carries only one drone. Constraint (13) states that the UAV only

visits one delivery point at a time. Constraint (14) states that no new drones take off during drone deliveries. Constraints (15)-(16) indicate that the pick-up point must be visited first, and then the delivery point must be visited. Constraints (17)-(20) are time synchronization constraints for trucks and UAVs. Constraints (21) and (22) define the time constraints for trucks to arrive at customer points. Constraints (23)-(24) define the time constraints for the UAV to reach the customer point. Constraints (25)-(26) represent time window constraints. Constraints (27) represent load constraints. Constraint (28) is the power constraint of the UAV.

3. Algorithm design of adaptive large neighborhood search

The pick-up and delivery vehicle routing problem with a time window in the “truck+drone” mode is an extension of the PDPTW problem, which is an NP-hard problem, and it is difficult to solve the problem in an acceptable time with precise algorithms and optimization solvers such as CPLEX large-scale examples. The ALNS algorithm can solve large-scale instances in a short period of time, so the article uses the ALNS algorithm to solve.

The ALNS algorithm is an adaptive large-neighborhood search algorithm that uses damage operators and repair operators to search the solution space. It was first proposed by Ropke on the basis of the large-neighborhood search algorithm. Delivery vehicle routing problem. In the search process, the algorithm adaptively selects the search operator according to the improvement of the operator to the solution, and the operator with a better improvement to the solution has a greater probability of being selected again to search for the solution in subsequent iterations, so as to achieve the optimal solution. The efficient search of the solution space improves the performance of the algorithm. In addition, in order to jump out of the local optimal solution, the algorithm also uses the new solution acceptance criterion of simulated annealing.

The algorithm framework of PDPTW-D is shown in Fig. 1: firstly, the greedy algorithm is used to construct the truck route, secondly, the ALNS is used to minimize the number of vehicles, thirdly, according to the UAV capacity constraints, time windows and other constraints, the delivery node is changed from truck access to UAV visits to save the path cost, finally, based on the fixed number of vehicles, the ALNS algorithm is applied to minimize the path cost. The repair operator used in the ALNS algorithm that minimizes the number of vehicles refers to the operator in the article of Ropke, which is optimized only for pure truck paths, the truck priority used in the ALNS algorithm that minimizes the path cost. The greedy repair operator and the truck-first regret value are inserted into the repair operator, which needs to consider the UAV path.

The article ALNS is shown in Algorithm 1. First, according to the operator weight, the roulette method is used to select the destruction operator and the repair operator to destroy and repair the current solution, and then apply the simulated annealing criterion to judge whether to accept the new solution. Finally, according to the iterative. In the process, each operator updates its weight on the improvement of the solution until the stopping criterion is satisfied. Each iteration the current temperature T drops to $T \cdot a$, a is the cooling rate of simulated annealing temperature, and the stopping criterion of the algorithm is the unimproved times of the current solution, the maximum total number of iterations and the longest running time of the algorithm.

Algorithm 1: ALNS Algorithm Framework

Inputs: initial temperature T_{init} , current truck route S , cooling rate a ,

Let $S_{best} = S$, $T = T_{init}$,

destruction operator $\sigma^- = \{1, \dots, 1\}$, repair operator $\sigma^+ = \{1, \dots, 1\}$,

do

Use the roulette method to select the damage operator d according to the operator weight, select the repair operator r according to the operator weight by the roulette method, $S'=r(d(S))$,

if $f(S') < f(S_{best})$ **then**

$S_{best}=S'$, update the operator weights in ω - and ω +,

end if

$T=T+a$,

while the stopping criterion is reached

return S_{best}

destruction operator

According to the characteristics of PDPTW-D problem, the requirements of correlation destroying operator and random destroying operator are put forward. Both operators destroy q requirements, q is 1 and q_{max} Random value between. When the pick-up point of a demand is destroyed, the corresponding delivery point is also destroyed.

(1) Correlation Destroyer

The correlation destroying operator was proposed by Shaw, which refers to destroying the current solution by destroying similar client nodes in the path. In the article, first randomly destroy a requirement, and then continuously destroy $q-1$ requirements with the highest similarity to this requirement. The similarity $R(i, j)$ between requirements i and j in the article is determined by three aspects: distance, time and load, and its calculation formula is as follows:

$$R(i, j) = \frac{(d_{A(i), A(j)} + d_{B(i), B(j)})}{(|T_{A(i)} - T_{A(j)}| + |T_{B(i)} - T_{B(j)}|) + |l_i - l_j|}$$

Among them, $A(i)$ and $B(i)$ represent the pick-up point and delivery point of demand i , $A(j)$ and $B(j)$ represent the pick-up point and delivery point of demand j , $d_{A(i), A(j)}$ and $d_{B(i), B(j)}$ are the distances between the pick-up point and the delivery point of demand i and j respectively, and $T_{A(i)}$ and $T_{B(i)}$ are respectively $T_{A(j)}$ and $T_{B(j)}$ are the time to reach the pick-up point and delivery point of demand j respectively. The smaller $R(i, j)$, the higher the similarity between requirement i and requirement j . If the take-off point or landing point of a delivery point delivered by a drone is destroyed, the delivery point and pick-up point of its corresponding demand will be destroyed. Correlation destruction operator is shown in Algorithm 2:

Algorithm 2: Correlation Destruction Operator

Input: the current route S , the demand quantity q that is planned to be destroyed,

Randomly select demand r from S and put it into array D , $D=\{r\}$,

while $|D|<q$

from array D Randomly select a demand r from among them,

Store the remaining demand in S in the array L in,

Arrange the array L according to the formula, $i<j$ means $R(r, L[i]) < R(r, L[j])$,

Randomly choose a number y from $0,1$, $D=D \cup \{L(y \cdot |L|)\}$,

end while

Destroy all requirements in D ,

if the takeoff point or landing point of the drone is destroyed **then**

The drone's access point and its corresponding pickup point were also compromised,

end if

return Route S composed of unbroken requirements

random damage operator

q requirements from the path. If the take-off point or landing point of the drone is destroyed in the original route, the corresponding pick-up point or delivery point should also be destroyed. The random destructor runs faster than the correlation destructor. Although poorer solutions may appear, it helps to search for diversity and jump out of local optimal solutions.

repair operator

The truck-priority greedy repair operator and the truck-priority regret value insertion repair operator used in this article are introduced in detail as follows: (1) Truck-first greedy repair operator

The truck-first greedy repair operator is divided into two steps: first insert all destroyed demand points into paths visited by trucks, and then change the delivery points accessible by drones from trucks to drones. Define Δf_{ik} is the change amount of the objective function after inserting the pick-up point i and the corresponding delivery point in the path k . In the process of constructing the route visited by trucks, the location of pick-up point i and its corresponding delivery point is given by $\min_k \Delta f_{ik}$. Decide. where $c_i = \min_{k \in K} \{\Delta f_{ik}\}$. The process of this operator is shown in Algorithm 3. In the process of changing the delivery nodes visited by trucks to UAVs, first construct the set C of all delivery points that UAVs can visit in the current solution. Then randomly select a node c in C , if cerator with truck priority and its pick-up point c' are only related to the truck, then judge whether it is possible to use drone delivery according to the path cost, and find the best location of these two customer nodes. Continue this method until all client nodes in set C are traversed. Retrieve the sort that yields the greatest savings, that is, the current solver case.

Algorithm 3: Truck-first greedy repair operator

Input: current route S , collection of uninserted pick-up points D ,

while $D \neq \emptyset$ **do**

Randomly select a pick-up point i in D , $D = D \setminus \{i\}$,

According to $\min_k \Delta f_{ik}$, $c_i = \min_{k \in K} \{\Delta f_{ik}\}$ insert the pick-up point i and its corresponding delivery point,

end while return S

C = all delivery points satisfying the drone capacity,

while $C \neq \emptyset$ **do**

Randomly select a point in C , $C = C \setminus \{c\}$,

if point c and its corresponding pick-up point c' are only related to the truck, that is, not the take-off point, landing point and access point of the drone **then**

$S' = S$, $S = S \setminus \{c, c'\}$, $f(S_1) = INF$,

for each path in S **do**

if current route capacity + $q_c + q_{c'} < Q$ **then**

All adjacent two node positions on **the for path do**

Construct the path $V = \langle i, c', i+1 \rangle$ for the truck to visit c' , the path $P = \langle m, c, m+1 \rangle$ for the drone to visit c , and the node position of point m is after point c' ,

if (c and c' satisfy the time window constraint in the path) && (UAV flight meets the endurance requirement) **then if** the newly constructed path cost $f(S_2) < f(S_1)$ **then**

$S_1 = S_2$,

end if end if

end for end if

end for return S_1 ,

if $f(S) < f(S')$ **then**

$S = S'$,

else

$S = S'$,

end if end while return S_{best}

(2) The regret value of truck priority is inserted into the repair operator

The implementation of this operator is divided into two steps. The first step is to insert all the destroyed pick-up points and delivery points in the way of truck delivery.

The fuzzy law can be derived as follows.

$$\begin{aligned}
 & 0 > \dot{V}(x) - \gamma_{50l}^2 \omega^T \omega + z^T z \\
 & = \dot{x}^T \nabla_x(x) - \gamma_{50l}^2 f \omega^T \omega + z^T z \\
 & = \frac{1}{g-1} \dot{x}^T \nabla_{xx} V(x) x - \gamma_{50l}^2 f \omega^T \omega + z^T z \\
 & = g \dot{x}^T P(x) x - \gamma_{50l}^2 f \omega^T \omega + z^T z \\
 & = \frac{g}{2} (x^T \bar{A}_{\mu\mu\mu}^T(x, y) P(x) x + \omega^T B_{\infty\mu}^T(x) P(x) x + *) + \bar{C}_{\mu\mu\mu}^d(x, y) \bar{C}_{\mu\mu\mu}(x, y) \\
 & = \begin{bmatrix} \bar{A}_{\mu\mu\mu}^T(x, y) \frac{g}{2} P(x) + \frac{g}{2} P(x) \bar{A}_{\mu\mu\mu}(x, y) + \bar{C}_{\mu\mu\mu}^d(x, y) \bar{C}_{\mu\mu\mu}(x, y) \\ D_{\infty\mu}^T(x) C_{\mu\mu\mu}(x, y) + B_{\infty\mu}^T(x) \frac{g}{2} P(x) \\ C_{\mu\mu\mu}^T(x) D_{\infty\mu}(x) + \frac{g}{2} P(x) B_{\infty\mu}(x) \\ D_{\infty\mu}^T(x) D_{\infty\mu}(x) + \gamma_{50l}^2 I \end{bmatrix} \begin{bmatrix} x \\ \omega \end{bmatrix}
 \end{aligned}$$

where

$$\begin{aligned}
 \Psi_u &= \begin{bmatrix} \begin{pmatrix} -A_s(x)G - G^T A_s^T(x) \\ -B_s(x)Z_s(x) - Z_s^T(x)B_s^T(x) \end{pmatrix} & \begin{pmatrix} P + G^T - \\ \zeta(A_s(x)G + B_s(x)Z_s(x)) \end{pmatrix} \\ * & \zeta(G + G^T) \\ * & * \\ * & * \\ -G^T B_{1s}^T(x) - Z_s^T(x)D_s^T(x) & -B_{\infty s}(x)H(x) \\ -\zeta(G^T C_{1s}^T(x) + Z_s^T(x)D_s^T(x)) & 0 \\ -\gamma^2 I & -D_{\infty s}(x)H(x) \\ * & I + H(x) + H^T(x) \end{bmatrix} \\
 \Psi_{ij} &= \begin{bmatrix} \begin{pmatrix} -A_s(x)G - G^T A_s^T(x) \\ -B_s(x)Z_j(x) - Z_j^T(x)B_s^T(x) \end{pmatrix} & \begin{pmatrix} P + G^T - \\ \zeta(A_s(x)G + B_s(x)Z_j(x)) \end{pmatrix} \\ * & \zeta(G + G^T) \\ * & * \\ * & * \\ -G^T C_{1s}^T(x) - Z_j^T(x)D_s^T(x) & -B_{\infty s}(x)H(x) \\ -\zeta(G^T C_{1s}^T(x) + Z_s^T(x)D_s^T(x)) & 0 \\ -\gamma^2 I & -D_{\infty s}(x)H(x) \\ * & I + H(x) + H^T(x) \end{bmatrix}
 \end{aligned}$$

$$\Psi_{ji} = \begin{bmatrix} \left(\begin{array}{c} -A_j(x)G - G^T A_j^T(x) \\ -B_s(x)Z_j(x) - Z_j^T(x)B_s^T(x) \end{array} \right) & \left(\begin{array}{c} P + G^T - \\ \zeta(A_j(x)G + B_j(x)Z_s(x)) \end{array} \right) \\ * & \zeta(G + G^T) \\ * & * \\ * & * \\ -G^T C_{ij}^T(x) - Z_s^T(x)D_j^T(x) & -B_{\infty s}(x)H(x) \\ -\zeta(G^T C_{ij}^T(x) + Z_i^T(x)D_j^T(x)) & 0 \\ -\gamma^2 I & -D_{\infty s}(x)H(x) \\ * & I + H(x) + H^T(x) \end{bmatrix}$$

4. Example

In order to verify the validity of the problem model and algorithm, the article has done the following two parts of experiments: (1) Comparing the solution results of 18 small-scale calculation examples of CPLEX and ALNS algorithms, it proves the validity of the model and algorithm, (2) Using The ALNS algorithm solves the medium-scale calculation example with 50 requirements and the large-scale calculation example with 100 requirements, verifies the stability of ALNS in solving large-scale problems, and analyzes the impact of the joint distribution mode of trucks and UAVs on path costs.

There is no ready-made calculation example for the PDPTW-D problem studied in this article, three types of calculations of cluster distribution C, random distribution R and random cluster distribution RC are generated based on the examples of Sacramento and Li. The example is used as the test case of the article. The location and demand of customer points in the calculation example. Fig. 2 is a schematic diagram of calculation example generation, (a) is a schematic diagram of VRP-D, (b) is a PDPTW-D after pairing of pick-up and delivery nodes and adding a time window schematic diagram. In Fig. 2, the square symbol represents the distribution center, the circle symbol represents the delivery point, the triangle symbol represents the pick-up point, the number above the symbol in Fig. (a) represents the demand, and the number (n, m, t) represent the demand, the lower limit of the time window and the upper limit of the time window, respectively.

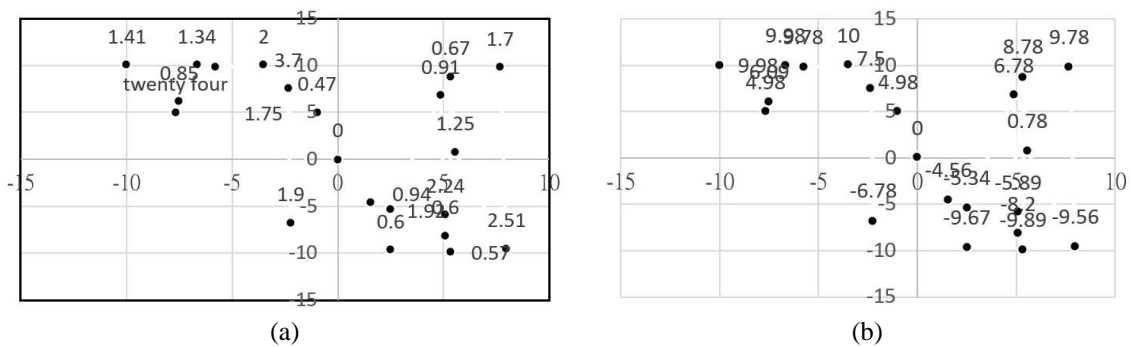


Fig. 2 Schematic diagram of calculation example generation

Table 1 The solution results of small-scale calculation examples

AC		CPLEX		ALNS			
lc15-2	2	438.91	712.81	2	438.91	2.01	0
lr15-1	3	399.22	3600	3	333.88	4.48	-16.37
lr15-2	4	386.30	3600	4	333.37	2.74	-13.70
lrc15-1	4	432.55	3600	4	420.89	3.08	-2.70
lrc15-2	5	568.31	3600	5	531.19	2.38	-6.53
lc20-1	2	454.85	3600	2	461.58	3.42	1.48
lc20-2	2	431.81	3600	2	431.68	4.57	-0.03
lr20-1	5	678.82	3600	5	548.76	3.67	-19.16
lr20-2	5	581.00	3600	5	470.31	5.19	-19.05
lrc20-1	7	1043.94	3600	7	847.77	3.64	-18.79
lrc20-2	7	956.86	3600	7	779.44	4.46	-18.54

Test environment and parameter settings.

The computer configuration of the experiment is Intel Core I 5-7200U 2.5G H z, 4 GB memory, ALNS is written in C++ language, IDE adopts Visio Studio 2019 and CPLEX adopts the default setting of CPLEX12.8.

ALNS in the article are set as follows: the total number of iterations is 15000, the maximum number of unimproved iterations is 2000, and the operator weight update criterion parameters $\sigma_1=33$, $\sigma_2=9$, $\sigma_3=13$. Simulated annealing temperature cooling rate $\alpha=0.99975$.

Due to the excessive constraints and parameters of the model, even the small-scale calculation example CPLEX solver cannot solve all of them accurately, some calculation examples cannot obtain the optimal solution within a limited time, and the improvement of the solution after 3600 seconds is small, so The article limits the maximum running time of CPLEX to 3600 seconds, and verifies the effectiveness of the ALNS algorithm by comparing the solution results of CPLEX within 3600 seconds and the solution results of ALNS. In Table 1 to Table 3, AC represents the name of the calculation example, RN represents the number of paths, TC represents the total cost, RT represents the running time, Gap represents the deviation between the solution result of the ALNS algorithm and the solution result of CPLEX, and its value is $(TC(ALNS)-TC(CPLEX))/TC(CPLEX)$.

18 small-scale calculation examples solved by CPLEX and ALNS are shown in Table 1. The bold font indicates the better running results of the two solution methods, and the negative Gap indicates that the solution effect of the ALNS algorithm is better than that of CPLEX. From the results, there are 11 cases where the ALNS results are better than the CPLEX results, and the cost difference is up to 19.16%, there are 6 cases where the ALNS results are the same as the CPLEX results, only 1 case has the ALNS results slightly worse than CPLEX. From the solution time point of view, the running time of ALNS is less than that of CPLEX. However, it is difficult for CPLEX to obtain the optimal solution for 20 requirements within 3600 seconds, while ALNS can obtain an accepted and effective solution within 5 seconds, which shows that the problem model proposed in the article and the ALNS algorithm are very effective for "truck+UAV". Pick-up and delivery path planning in mode is effective.

In order to verify the stability of the ALNS algorithm for medium-scale and large-scale calculation examples, and analyze the impact of the joint distribution mode of trucks and drones on the route cost, the article analyzed three different types of type C, type R, and type RC, and 18

Table 2 Solution results of 50 groups of customer points

AC	Z PDPTW	Z IN	Z PDPTW-D	GAPI (%)	GAPD (%)
lc5_1	306.96	334.79	213.59	36.2	30.42
lc5_2	308.87	253.33	238.15	5.99	22.90
lc5_3	533.63	432.75	351.61	18.75	34.11
lc5_4	509.11	401.22	388.98	3.05	23.60
lc5_5	660.95	635.40	451.76	28.90	31.65
lc5_6	680.31	750.74	485.96	35.27	28.57
lr5_1	328.28	311.25	245.80	21.03	25.12
lr5_2	325.13	351.33	298.02	15.17	8.34
lr5_3	589.74	405.46	303.30	25.20	48.57
lr5_4	592.27	508.03	401.97	20.88	32.13
lr5_5	662.28	706.03	523.64	25.83	20.93
lr5_6	689.47	878.76	634.85	27.76	7.92
lrc5_1	324.99	289.89	267.58	7.70	17.67
lrc5_2	324.92	302.05	262.41	13.12	19.24
lrc5_3	586.11	426.83	359.71	15.73	38.63
lrc5_4	573.41	537.83	394.73	26.61	31.16
lrc5_5	673.99	744.16	482.48	35.16	28.41
lrc5_6	654.64	641.31	581.38	9.34	11.19

Table 3 Solution results of 100 groups of customer points

AC	Z PDPTW	Z IN	Z PDPTW-D	GAPI (%)	GAPD (%)
lc10_1	618.79	484.32	318.85	34.17	48.47
lc10_2	625.86	469.37	382.40	18.53	38.90
lc10_3	849.94	831.39	536.26	35.5	36.91
lc10_4	881.86	531.23	529.49	0.33	39.96
lc10_5	1303.36	1354.55	939.58	30.64	27.91
lc10_6	1270.10	1198.80	1095.59	8.61	13.74
lr10_1	653.58	503.07	408.28	18.84	37.53
lr10_2	629.12	503.91	437.12	13.25	30.52
lr10_3	1004.71	954.70	775.77	18.74	22.79
lr10_4	964.50	695.96	494.30	28.98	48.75
lr10_5	1348.08	1217.99	936.20	23.14	30.55
lr10_6	1310.74	1222.66	1091.43	10.73	16.73
lrc10_1	650.91	440.29	419.38	4.75	35.57
lrc10_2	625.76	572.70	420.67	26.55	32.77
lrc10_3	965.61	772.57	543.80	29.61	43.68
lrc10_4	936.99	784.86	725.66	7.54	22.55
lrc10_5	1371.91	1257.49	961.66	23.53	29.90
lrc10_6	1354.43	1096.57	1017.47	7.21	24.88

groups of 50 and 100 requirements are tested, and the calculation results are shown in Table 2 and Table 3.

In Table 2 and Table 3, Z IN Indicates the path cost of the initial solution in the joint

distribution mode of trucks and UAVs, Z PDPTW Indicates the path cost for truck- only deliveries, Z PDPTW-D Indicates the path cost of the final solution in the joint distribution mode of trucks and UAVs, GAPI means and Z IN Compared to Z PDPTW-D Saved path cost, its value is $(Z IN - Z PDPTW-D) / Z IN$, GAPD is expressed with Z PDPTW Compared to Z PDPTW-D The path cost saved is $(Z PDPTW - Z PDPTW-D) / Z PDPTW$.

It can be seen from Table 2 that the GAPI and GAPD values of the three different types of data of R, C and RC are greater than 0. The ALNS algorithm improves the initial solution by 15%-30%, and the initial solution is increased by 36.20% at the highest, indicating that ALNS can avoid local optimum and obtain a better solution, the joint distribution mode of trucks and drones saves path costs 15%-35%, the highest saving is 48.57%, indicating that the joint distribution of trucks and drones can save a lot of path costs compared with pure truck distribution, and the effectiveness and necessity of drones for medium-scale PDPTW problems.

from table 3 It can be seen in R class, C class, RC Three different types of data are derived from GAPI and GAPD Values greater than 0, ALNS

Improve the initial solution by about 5%-30%, ALNS The highest improvement of the initial solution is 34.17%, indicating that ALNS In avoiding local optima and obtaining better

The effectiveness of the solution, the joint distribution of trucks and drones saves 20%-40% of the path cost, and the maximum savings is 48.75%, indicating that the joint distribution of trucks and drones can save a lot of route costs compared with pure truck distribution., the effectiveness and necessity of UAVs for large-scale PDPTW problems.

By testing and solving three different types of medium-scale and large-scale calculation examples of type C, type R, and type RC, it can be seen that the ALNS algorithm improves the initial solution by about 15%-30%, and the performance of the algorithm is relatively stable. ALNS can Avoid local optima and obtain a better solution, the joint distribution of trucks and UAVs saves about 20%-35% of the path cost, indicating that the “truck+UAV” transportation mode can save a lot of path costs. In PDPTW In the problem, using the “truck+UAV” transportation mode can solve different types and different scales of calculation examples, and provide decision-making basis for the path planning of the actual “truck+UAV” mode for picking and delivering goods.

5. Conclusions

The PDPTW-D problem was studied, and the model of the model was proposed. By designing a variety of efficient damage operators and repair operators based on the characteristics of the model, an adaptive large neighborhood search algorithm was designed to solve it, and the simulated annealing algorithm was used to solve the problem. Prevent the algorithm from getting stuck locally. The efficiency of the algorithm is verified by comparing the running results of small-scale calculation examples with CPLEX, and the stability and effectiveness of the algorithm are verified through medium-scale calculation examples and large-scale calculation examples. Through the analysis of the results, the joint distribution model of trucks and UAVs can effectively reduce the path cost. In practical applications, it can improve the efficiency of picking and delivering goods in the logistics network and provide a basis for the path planning of the “truck+UAV” model. Decision basis. Subsequent research questions will consider the impact of cargo weight on truck transportation rate and UAV transportation mileage, as well as factors such as soft time windows, to enrich the research scenarios of the problem.

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