

Distributed Perimeter Control for Urban Road Network Considering Heterogeneous Cordon Traffic Conditions

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- Centralized control framework lacks scalability and transferability



$$r_{i,t}' = \begin{cases} 1 & , D \\ 0 & , D \\ -1 & , D \end{cases}$$

$$r_{i,t}^{\prime\prime} = \begin{cases} 0 & , O_{i,t} \\ -1 & , O_{i,t} \end{cases}$$

$$r_{i,t}^{\prime \prime \prime} = \begin{cases} 0 & , n_{i,t}^{2} \\ -1 & , n_{i,t}^{2} \end{cases}$$

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N-TTD veh∙m)	EN-TTT (10 ⁵ veh⋅s)	Total cordon queue (10 ⁵ veh⋅s)	Conclusions
2.06	239.93	75.02	 Compared with b decreases th cordon queue improves bot distributed training
2.67	373.86	108.26	
23.19	327.35	114.96	
24.63	457.73	203.34	
3.59	340.43	113.05	

