## LIST OF FIGURES

Fig. No.	Figure Title	Pago No.
Fig. 1.1	Pictorial Representation of degree of membership	9
Fig. 2.1	Different shapes obtained by varying the value of fuzzification factor m	28
Fig. 2.2	Link Preference Index diagram	32
Fig. 2.3	Network for FSPP	36
Fig. 2.4	Ranking of paths in the network	40
Fig. 2.5	Network for FMST	44
Fig. 2.6	Fuzzy Minimum Spanning Tree for the given network	47
Fig. 2.7	Network for FSTP with Steiner points shown as double circles	48
Fig. 2.8	Fuzzy complete undirected distance graph $G_1$	50
Fig. 2.9	Fuzzy Minimal Spanning Tree $T_1$ of $G_1$	53
Fig. 2.10	Final Fuzzy Steiner Tree $(T_{FS})$	53
Fig. 2.11(a)	Behavior in terms of cost of shortest path shown by different ranking methods by varying the delay requirement on a random graph with 250 nodes generated by gengraph-win	66
Fig. 2.11(b)	Behavior in terms of path discretization error shown by different ranking methods by varying the delay requirement on a random graph with 250 nodes generated by gengraph-win	66
Fig. 2.11(c)	Behavior in terms of CPU Execution time shown by different ranking methods by varying the delay requirement on a random graph with 250 nodes generated by gengraph-win	67
Fig. 2.12	The point considered as Circumcenter of Centroid (COC) is shown by $\boldsymbol{X}$	67
Fig. 2.13	A surface plot with the delay requirement, cost and CPU execution time of WF	68

Fig. 2.14	Box and Whisker plot showing the fuzzy cost as a TFN with four parameters at the delay requirement = 30 units	68
Fig. 2.15	Block diagram of a typical Wireless Sensor node (mote)	71
Fig. 2.16	A Wireless Sensor Network (WSN) represented as a Unit Disc Graph (UDG)	71
Fig. 2.17	Pictorial representation of trapezoidal fuzzy number	72
Fig. 2.18	(a) Behaviour of the CFSPP algorithm when applied on a graph with 200 nodes generated using gengraph-win with source (s) = 45 and target (t) = 68, (b) Comparison of the same behaviour for four different network sizes with source (s) = 4 and target (t) = 45	74
Fig. 2.19	Progress of the CFSPP algorithm in terms of energy consumption with a strict and a relaxed delay constraint when applied on a graph with 200 nodes generated using gengraphwin	76
Fig. 2.20	Progress of the CFSPP algorithm in terms of path delay with delay constraint= 350 when applied on a graph with 50, 100, 150, 200 nodes generated using gengraph-win	76
Fig. 2.21	Membership Function for total collected score of a path	82
Fig. 2.22	Membership Function for total time taken to traverse a path	82
Fig. 2.23	Fuzzy decision set $Z$ and $Z^*$	83
Fig. 2.24	Input Graph $G(V, E)$ with source vertex = 1 and destination vertex = 5	84
Fig. 2.25	Several steps of the parallel formulation of FOP	92
Fig. 3.1	Trapezoidal intuitionistic fuzzy number (TIFN)	104
Fig. 3.2	The point of reference used for ranking a TIFN	107
Fig. 3.3	Behaviour shown by the cost of the shortest path on varying the input delay constraint for a graph with 200 nodes generated using <i>gengraph-win</i>	113
Fig. 3.4	Quasi-Gaussian Intuitionistic Fuzzy Number	115
Fig. 3.5	Centroid method of ranking for QGIFN	116

Fig. 3.6	Trend observed in the cost of the shortest path on varying the input delay constraint for a graph with 100 nodes generated using gengraph-win	121
Fig. 3.7	The input graph with $N = 5$ , $v_1 = 1$ , $v_N = 5$ and the time and score values associated with each edge and vertex respectively	123
Fig. 3.8	The sequential module executing step 1 of IFOP that computes all the distinct paths in the given graph $G$	130
Fig. 3.9	The parallel version of IFOP along with its work-depth analysis stating the work and depth value of each step	131
Fig. 3.10	Input graph $G$ with number of nodes $(N)=5$ , source $(v_1)=1$ , target $(v_N)=5$ and the co-ordinate values (intuitionistic fuzzy points) and the score values (trapezoidal intuitionistic fuzzy numbers) of each node	139
Fig. 4.1	Comparison of the maximum value of the total collected score obtained by four different selection methods for different $T_{max}$ values (160 cities)	158
Fig. 4.2	Comparison of the maximum value of the total collected score obtained by four different selection methods for different $T_{max}$ values (306 cities)	159
Fig. 4.3	Graph for (a) 160 cities and (b) 306 cities instance	160
Fig. 4.4	The process of selecting a path using roulette wheel selection function where the number in () denotes the probability of node selection	162
Fig. 4.5	Progression of RWS_OP algorithm for a graph with 25 nodes	169
	with source $(V_1) = 1$ , destination $(V_N) = 25$ and $T_{max} = 70$	
Fig. 4.6	with source $(V_1) = 1$ , destination $(V_N) = 25$ and $T_{max} = 70$ Comparison of (a) maximum score and (b) mean score of each method with respect to time budget $(T_{max})$	173
Fig. 4.6 Fig. 4.7	Comparison of (a) maximum score and (b) mean score of each	173 174
-	Comparison of (a) maximum score and (b) mean score of each method with respect to time budget $(T_{max})$ Comparison of execution time of each method with respect to time budget $(T_{max})$ based on 30 runs at $\alpha = 0.6$ for Real Road	
Fig. 4.7	Comparison of (a) maximum score and (b) mean score of each method with respect to time budget $(T_{max})$ Comparison of execution time of each method with respect to time budget $(T_{max})$ based on 30 runs at $\alpha = 0.6$ for Real Road Network database with 306 cities of Poland  Comparison of score with respect to $\alpha$ for (a) $T_{max} = 1500$ and (b) $T_{max} = 2500$ for a Real Road Network database	174

Fig. 4.10 Plots showing the observation of three different runs of 180 RWS\_OP with  $\alpha = 0.2$  and  $T_{max} = 1500$  for a Real Road Network database with 160 cities of Poland. As the algorithm progresses, it results in (a) decrease in the time budget and (b) increase in the total collected score as shown above Fig. 4.11 Plots showing (a) utilization of the time budget and (b) 181 increase in the total collected score for three different  $\alpha$  values at  $T_{max} = 1500$  for a Real Road Network database with 160 cities of Poland Fig. 4.12 182 Plots showing (a) the percentage of nodes explored with the increase in  $T_{max}$  values at  $\alpha = 0.6$  and (b) percentage of nodes explored and unexplored for different values of  $\alpha$  at  $T_{max}$  = 7000 for a Real Road Network database with 160 cities of Poland for 30 runs Fig. 4.13 Plot showing that RWS\_OP can achieve higher total collected 184 score for larger  $T_{max}$  values as compared to Ostrowski\_CG and Ostrowski IG methods when implemented on a Real Road Network database with 306 cities of Poland at  $\alpha = 0.6$ Fig. 4.14 Comparison of the total collected score value achieved by 189 GRASP and FPA algorithms for different  $T_{max}$  values when applied on a graph with 102 nodes, source=1, destination=102 Fig. 4.15 Comparison of the average execution time (s) of the CSPP 197 algorithm suggested by Chen et al. (2008) with the bidirectional search algorithm for different network sizes