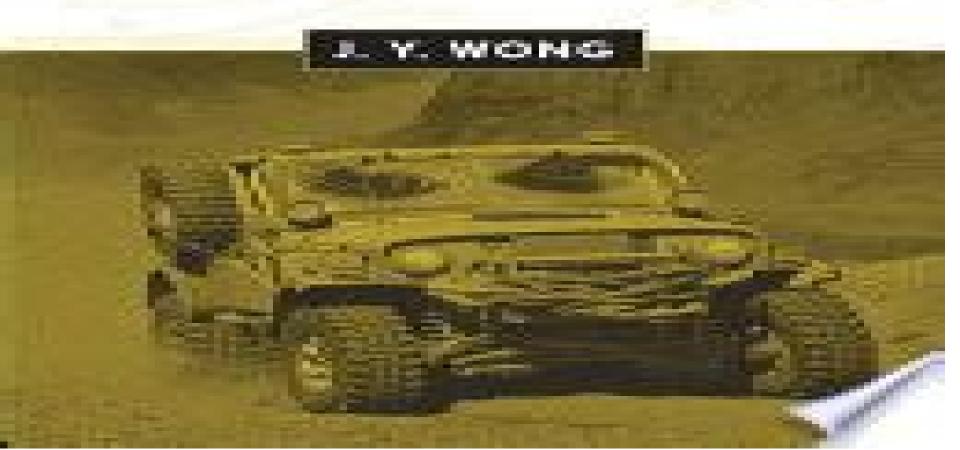
GROUND VEHICLES



Theory Ground Vehicles J Wong

Eric F. Thacher

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research design and tests based on energy efficiency vehicle dynamics and operational properties requirements This volume addresses fundamental engineering problems including how to investigate the effect of different driveline systems on the properties of vehicles and how to determined the optimal characteristics of the driveline system and its power dividing units PDUs and design it for a specific vehicle to ensure high level of vehicle dynamics energy efficiency and performance The authors develop an analytical apparatus for math modeling of driveline systems that can be compiled from different types of PDUs They also introduce methodologies for the synthesis of optimal characteristics of PDUs for different types of vehicles Structured to be useful to engineers of all levels of experience university professors and graduate students the book is based on the R D projects conducted by the authors It explores intriguing engineering dilemmas such as how to achieve higher energy and fuel efficiency by driving either all the wheels or not all the wheels solve oversteering issues by managing wheel power distribution and many other technical problems A Solar Car Primer Eric F. Thacher, 2003 In the quixotic quest to reduce air pollution and fuel cars with alternative sources instead of gas solar powered cars have emerged as one option Although disagreements abound about the feasibility and practicality of these vehicles this book presents the basics behind the idea of solar cars From the construction of the engine to raising funds the book is a valuable introduction to the present and future of the emission free automobile Advanced Autonomous Vehicle Design for Severe Environments V.V. Vantsevich, M.V. Blundell, 2015-10-20 Classical vehicle dynamics which is the basis for manned ground vehicle design has exhausted its potential for providing novel design concepts to a large degree At the same time unmanned ground vehicle UGV dynamics is still in its infancy and is currently being developed using general analytical dynamics principles with very little input from actual vehicle dynamics theory This technical book presents outcomes from the NATO Advanced Study Institute ASI Advanced Autonomous Vehicle Design for Severe Environments held in Coventry UK in July 2014 The ASI provided a platform for world class professionals to meet and discuss leading edge research engineering accomplishments and future trends in manned and unmanned ground vehicle dynamics terrain mobility and energy efficiency The outcomes of this collective effort serve as an analytical foundation for autonomous vehicle design Topics covered include historical aspects pivotal accomplishments and the analysis of future trends in on and off road manned and unmanned vehicle dynamics terramechanics soil dynamic characteristics uncertainties and stochastic characteristics of vehicle environment interaction for agile vehicle dynamics modeling new methods and techniques in on line control and learning for vehicle autonomy fundamentals of agility and severe environments mechatronics and cyber physics issues of agile vehicle dynamics to design for control energy harvesting and cyber security and case studies of agile and inverse vehicle dynamics and vehicle systems design including optimisation of suspension and driveline systems. The book targets graduate students who desire to advance further in leading edge vehicle dynamics topics in manned and unmanned ground vehicles PhD students continuing their research work and building advanced curricula in academia and industry and researchers in government agencies and

private companies Management Information And Optoelectronic Engineering - Proceedings Of The 2016 International <u>Conference</u> Yongsheng Gao, 2017-03-14 This proceedings brings together 59 selected articles presented at the joint conferences of the International Conference on Management Information and Communication ICMIC2016 and the International Conference on Optics and Electronics Engineering ICOEE2016 which were held in Guilin China during May 28 29 2016 ICMIC2016 and ICOEE2016 provide a platform for researchers engineers academicians as well as industrial professionals from all over the world to present their latest findings and results in the development in Information Management Communication Optics and Electronics host by ICMIC2016 and ICOEE2016 The proceedings collected the latest research results and applications in the related areas We hope to enlighten readers with some latest developments in Information Management and Optics Electronics presented at the joint conferences **Autonomous Vehicle Maneuvering** at the Limit of Friction Victor Fors, 2020-10-23 Without a driver to fall back on a fully self driving car needs to be able to handle any situation it can encounter With the perspective of future safety systems this research studies autonomous maneuvering at the tire road friction limit In these situations the dynamics is highly nonlinear and the tire road parameters are uncertain To gain insights into the optimal behavior of autonomous safety critical maneuvers they are analyzed using optimal control Since analytical solutions of the studied optimal control problems are intractable they are solved numerically An optimization formulation reveals how the optimal behavior is influenced by the total amount of braking By studying how the optimal trajectory relates to the attainable forces throughout a maneuver it is found that maximizing the force in a certain direction is important This is like the analytical solutions obtained for friction limited particle models in earlier research and it is shown to result in vehicle behavior close to the optimal also for a more complex model Based on the insights gained from the optimal behavior controllers for autonomous safety maneuvers are developed. These controllers are based on using acceleration vector references obtained from friction limited particle models Exploiting that the individual tire forces tend to be close to their friction limits the desired tire slip angles are determined for a given acceleration vector reference This results in controllers capable of operating at the limit of friction at a low computational cost and reduces the number of vehicle parameters used For straight line braking ABS can intervene to reduce the braking distance without prior information about the road friction Inspired by this a controller that uses the available actuation according to the least friction necessary to avoid a collision is developed resulting in autonomous collision avoidance without any estimation of the tire road friction Investigating time optimal lane changes it is found that a simple friction limited particle model is insufficient to determine the desired acceleration vector but including a jerk limit to account for the yaw dynamics is sufficient To enable a tradeoff between braking and avoidance with a more general obstacle representation the acceleration vector reference is computed in a receding horizon framework The controllers developed in this thesis show great promise with low computational cost and performance not far from that obtained offline by using numerical optimization when evaluated in

high fidelity simulation Nonlinear Dynamics of Longitudinal Ground Vehicle Traction Brian John Olson, 2001

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