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Vehicle Dynamics Reza N. Jazar,2013-11-19 This textbook is appropriate for senior undergraduate and first year graduate students in mechanical and automotive engineering. The contents in this book are presented at a theoretical-practical level. It explains vehicle dynamics concepts in detail, concentrating on their practical use. Related theorems and formal proofs are provided, as are real-life applications. Students, researchers and practicing engineers alike will appreciate the user-friendly presentation of a wealth of topics, most notably steering, handling, ride, and related components. This book also: Illustrates all key concepts with examples Includes exercises for each chapter Covers front, rear, and four wheel steering systems, as well as the advantages and disadvantages of different steering schemes Includes an emphasis on design throughout the text, which provides a practical, hands-on

approach

On motion planning and control for truck and trailer systems Oskar Ljungqvist, 2019-01-22 During the last decades, improved sensor and hardware technologies as well as new methods and algorithms have made self-driving vehicles a realistic possibility in the near future. Thanks to this technology enhancement, many leading automotive and technology companies have turned their attention towards developing advanced driver assistance systems (ADAS) and self-driving vehicles. Autonomous vehicles are expected to have their first big impact in closed areas, such as mines, harbors and loading/offloading sites. In such areas, the legal requirements are less restrictive and the surrounding environment is more controlled and predictable compared to urban areas. Expected positive outcomes include increased productivity and safety, reduced emissions and the possibility to relieve the human from performing complex or dangerous tasks. Within these sites, different truck and trailer systems are used to transport materials. These systems are composed of several interconnected modules, and are thus large and highly unstable while reversing. This thesis addresses the problem of designing efficient motion planning and feedback control frameworks for such systems. First, a cascade controller for a reversing truck with a dolly-steered trailer is presented. The unstable modes of the system is stabilized around circular equilibrium configurations using a gain-scheduled linear quadratic (LQ) controller together with a higher-level pure pursuit controller to enable

path following of piecewise linear reference paths. The cascade controller is then used within a rapidly-exploring random tree (RRT) framework and the complete motion planning and control framework is demonstrated on a small-scale test vehicle. Second, a path following controller for a reversing truck with a dolly-steered trailer is proposed for the case when the obtained motion plan is kinematically feasible. The control errors of the system are modeled in terms of their deviation from the nominal path and a stabilizing LQ controller with feedforward action is designed based on the linearization of the control error model. Stability of the closed-loop system is proven by combining global optimization, theory from linear differential inclusions and linear matrix inequality techniques. Third, a systematic framework is presented for analyzing stability of the closed-loop system consisting of a controlled vehicle and a feedback controller, executing a motion plan computed by a lattice planner. When this motion planner is considered, it is shown that the closed-loop system can be modeled as a nonlinear hybrid system. Based on this, a novel method is presented for analyzing the behavior of the tracking error, how to design the feedback controller and how to potentially impose constraints on the motion planner in order to guarantee that the tracking error is bounded and decays towards zero. Fourth, a complete motion planning and control solution for a truck with a dolly-steered trailer is presented. A lattice-based motion planner is proposed, where a novel parametrization of the vehicle's state-space is

proposed to improve online planning time. A time-symmetry result is established that enhance the numerical stability of the numerical optimal control solver used for generating the motion primitives. Moreover, a nonlinear observer for state estimation is developed which only utilizes information from sensors that are mounted on the truck, making the system independent of additional trailer sensors. The proposed framework is implemented on a full-scale truck with a dolly-steered trailer and results from a series of field experiments are presented.

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recognizing design, feature and product innovation, has become the gold standard against which all other outdoor-industry awards are measured.

Motion planning and feedback control techniques with applications to long tractor-trailer vehicles

Oskar Ljungqvist, 2020-04-20 During the last decades, improved sensor and hardware technologies as well as new methods and algorithms have made self-driving vehicles a realistic possibility in the near future. At the same time, there has been a growing demand within the transportation sector to increase efficiency and to reduce the environmental impact related to transportation of people and goods. Therefore, many leading automotive and technology companies have turned their attention towards developing advanced driver assistance systems and self-driving vehicles. Autonomous vehicles are expected to have their first big impact in closed environments, such as mines, harbors, loading and offloading sites. In such areas, the legal requirements are less restrictive and the surrounding environment is more controlled and predictable compared to urban areas. Expected positive outcomes include increased productivity and safety, reduced emissions and the possibility to relieve the human from performing complex or dangerous tasks. Within these sites, tractor-trailer vehicles are frequently used for transportation. These vehicles are composed of several interconnected vehicle segments, and are therefore large, complex and unstable while reversing. This thesis addresses the problem of designing efficient motion planning

and feedback control techniques for such systems. The contributions of this thesis are within the area of motion planning and feedback control for long tractor-trailer combinations operating at low-speeds in closed and unstructured environments. It includes development of motion planning and feedback control frameworks, structured design tools for guaranteeing closed-loop stability and experimental validation of the proposed solutions through simulations, lab and field experiments. Even though the primary application in this work is tractor-trailer vehicles, many of the proposed approaches can with some adjustments also be used for other systems, such as drones and ships. The developed sampling-based motion planning algorithms are based upon the probabilistic closed-loop rapidly exploring random tree (CL-RRT) algorithm and the deterministic lattice-based motion planning algorithm. It is also proposed to use numerical optimal control offline for precomputing libraries of optimized maneuvers as well as during online planning in the form of a warm-started optimization step. To follow the motion plan, several predictive path-following control approaches are proposed with different computational complexity and performance. Common for these approaches are that they use a path-following error model of the vehicle for future predictions and are tailored to operate in series with a motion planner that computes feasible paths. The design strategies for the path-following approaches include linear quadratic (LQ) control and several advanced model predictive

control (MPC) techniques to account for physical and sensing limitations. To strengthen the practical value of the developed techniques, several of the proposed approaches have been implemented and successfully demonstrated in field experiments on a full-scale test platform. To estimate the vehicle states needed for control, a novel nonlinear observer is evaluated on the full-scale test vehicle. It is designed to only utilize information from sensors that are mounted on the tractor, making the system independent of any sensor mounted on the trailer. Under de senaste årtiondena har utvecklingen av sensor- och hårdvaruteknik gått i en snabb takt, samtidigt som nya metoder och algoritmer har introducerats. Samtidigt ställs det stora krav på transportsektorn att öka effektiviteten och minska miljöpåverkan vid transporter av både människor och varor. Som en följd av detta har många ledande fordonstillverkare och teknikföretag börjat satsa på att utveckla avancerade förarstödsystem och självkörande fordon. Även forskningen inom autonoma fordon har under de senaste årtiondena kraftigt ökat då en rad tekniska problem återstår att lösas. Förarlösa fordon förväntas få sitt första stora genombrott i slutna miljöer, såsom gruvor, hamnar, lastnings- och lossningsplatser. I sådana områden är lagstiftningen mindre hård jämfört med stadsområden och omgivningen är mer kontrollerad och förutsägbar. Några av de förväntade positiva effekterna är ökad produktivitet och säkerhet, minskade utsläpp och möjligheten att avlasta människor från att utföra svåra eller farliga uppgifter. Inom dessa platser

används ofta lastbilar med olika släpvagnskombinationer för att transportera material. En sådan fordonskombination är uppbyggd av flera ihopkopplade moduler och är således utmanande att backa då systemet är instabilt. Detta gör det svårt att utforma ramverk för att styra sådana system vid exempelvis autonom backning. Självkörande fordon är mycket komplexa system som består av en rad olika komponenter vilka är designade för att lösa separata delproblem. Två viktiga komponenter i ett självkörande fordon är dels rörelseplaneraren som har i uppgift att planera hur fordonet ska röra sig för att på ett säkert sätt nå ett överordnat mål, och dels den banföljande regulatorn vars uppgift är att se till att den planerade manövern faktiskt utförs i praktiken trots störningar och modellfel. I denna avhandling presenteras flera olika algoritmer för att planera och utföra komplexa manövrar för lastbilar med olika typer av släpvagnskombinationer. De presenterade algoritmerna är avsedda att användas som avancerade förarstödsystem eller som komponenter i ett helt autonomt system. Även om den primära applikationen i denna avhandling är lastbilar med släp, kan många av de förslagna algoritmerna även användas för en rad andra system, så som drönare och båtar. Experimentell validering är viktigt för att motivera att en föreslagen algoritm är användbar i praktiken. I denna avhandling har flera av de föreslagna planerings- och reglerstrategierna implementerats på en småskalig testplattform och utvärderats i en kontrollerad labbmiljö. Utöver detta har även flera av de

föreslagna ramverken implementerats och utvärderats i fältexperiment på en fullskalig test-plattform som har utvecklats i samarbete med Scania CV. Här utvärderas även en ny metod för att skatta släpvagnens beteende genom att endast utnyttja information från sensorer monterade på lastbilen, vilket gör det föreslagna ramverket oberoende av sensorer monterade på släpvagnen.

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Emergency Response Guidebook U.S. Department of Transportation,2013-06-03 Does the identification number 60 indicate a toxic substance or a flammable solid, in the molten state at an elevated temperature? Does the identification number 1035 indicate ethane or butane? What is the difference between natural gas transmission pipelines and natural gas distribution pipelines? If you came upon an overturned truck on the highway that was leaking, would you be able to identify if it was hazardous and know what steps to take? Questions like these and more are answered in the Emergency Response Guidebook. Learn how to identify symbols for and vehicles carrying toxic, flammable, explosive, radioactive, or otherwise harmful substances and how to respond once an incident involving those substances has been identified. Always be prepared in situations that are unfamiliar and dangerous and know how to

rectify them. Keeping this guide around at all times will ensure that, if you were to come upon a transportation situation involving hazardous substances or dangerous goods, you will be able to help keep others and yourself out of danger. With color-coded pages for quick and easy reference, this is the official manual used by first responders in the United States and Canada for transportation incidents involving dangerous goods or hazardous materials.

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CDL Study Guide Book CDL Test Prep Team, 2016-03
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Commerce Business Daily ,1998-07

Los Angeles Magazine ,2005-06 Los Angeles magazine is a regional magazine of national stature. Our combination of award-winning feature writing, investigative reporting, service journalism, and design covers the people, lifestyle, culture, entertainment, fashion, art and architecture, and news that define Southern California. Started in the spring of 1961, Los Angeles magazine has been addressing the needs and interests of our region for 48 years. The magazine continues to be the definitive resource for an affluent population that is intensely interested in a lifestyle that is uniquely Southern Californian.

Theory of Ground Vehicles J. Y. Wong,2001-03-20

An updated edition of the classic reference on the dynamics of road and off-road vehicles As we enter a new millennium, the vehicle industry faces greater challenges than ever before as it strives to meet the increasing demand for safer, environmentally friendlier, more energy efficient, and lower emissions products. Theory of Ground

Vehicles, Third Edition gives aspiring and practicing engineers a fundamental understanding of the critical factors affecting the performance, handling, and ride essential to the development and design of ground vehicles that meet these requirements. As in previous editions, this book focuses on applying engineering principles to the analysis of vehicle behavior. A large number of practical examples and problems are included throughout to help readers bridge the gap between theory and practice. Covering a wide range of topics concerning the dynamics of road and off-road vehicles, this Third Edition is filled with up-to-date information, including: * The Magic Formula for characterizing pneumatic tire behavior from test data for vehicle handling simulations * Computer-aided methods for performance and design evaluation of off-road vehicles, based on the author's own research * Updated data on road vehicle transmissions and operating fuel economy * Fundamentals of road vehicle stability control * Optimization of the performance of four-wheel-drive off-road vehicles and experimental substantiation, based on the author's own investigations * A new theory on skid-steering of tracked vehicles, developed by the author.

Los Angeles Magazine, 2000-04 *Los Angeles magazine* is a regional magazine of national stature. Our combination of award-winning feature writing, investigative reporting, service journalism, and design covers the people, lifestyle, culture, entertainment, fashion, art and architecture, and news that define Southern California. Started in the spring of 1961, *Los*

Angeles magazine has been addressing the needs and interests of our region for 48 years. The magazine continues to be the definitive resource for an affluent population that is intensely interested in a lifestyle that is uniquely Southern Californian.

Popular Science ,2006

Best Life ,2006-06 Best Life magazine empowers men to continually improve their physical, emotional and financial well-being to better enjoy the most rewarding years of their life.

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