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**Yi-Tong Ma**

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*Standards for Vocational Truck-Tractor-Trailer Service Instruction* Motor Vehicle Manufacturers Association of the United States, Motor Vehicle Manufacturers Association of the United States. Service Managers Committee, American Vocational Association, 1982-12-01

**Technologies and Approaches to Reducing the Fuel Consumption of Medium- and Heavy-Duty Vehicles** National Research Council, Transportation Research Board, Division on Engineering and Physical Sciences, Board on Energy and Environmental Systems, Committee to Assess Fuel Economy Technologies for Medium- and Heavy-Duty Vehicles, 2010-08-30 Technologies and Approaches to Reducing the Fuel Consumption of Medium- and Heavy-Duty Vehicles evaluates various technologies and methods that could improve the fuel economy of medium- and heavy-duty vehicles, such as tractor-trailers, transit buses, and work trucks. The book also recommends approaches that federal agencies could use to regulate these vehicles' fuel consumption. Currently there are no fuel consumption standards for such vehicles, which account for about 26 percent of the transportation fuel used in the U.S. The miles-per-gallon measure used to regulate the fuel economy of passenger cars. is not appropriate for medium- and heavy-duty vehicles, which are designed above all to carry loads efficiently. Instead, any regulation of medium- and heavy-duty vehicles should use a metric that reflects the efficiency with which a vehicle moves goods or passengers, such as gallons per ton-mile, a unit that reflects the amount of fuel a vehicle would use to carry a ton of goods one mile. This is called load-specific fuel consumption (LSFC). The book estimates the improvements that various technologies could achieve over the next decade in seven vehicle types. For example, using advanced diesel engines in tractor-trailers could lower their fuel consumption by up to 20 percent by 2020, and improved aerodynamics could yield an 11 percent reduction. Hybrid powertrains could lower the fuel consumption of vehicles that stop frequently, such as garbage trucks and transit buses, by as much 35 percent in the same time frame.

CDL Study Guide Book CDL Test Prep Team, 2016-03 Test Prep Book's CDL Study Guide Book: Test Preparation & Training Manual for the Commercial Drivers License (CDL) Exam Developed by Test Prep Books for test takers trying to achieve a passing score on the CDL exam, this comprehensive study guide includes: -Quick Overview -Test-Taking Strategies -Introduction -Driving Safely -Transporting Cargo Safely -Transporting Passengers Safely -Air Brakes -Combination Vehicles -Doubles and Triples -Tank Vehicles -Hazardous Materials -School Buses -Pre-Trip Vehicle Inspection Test -Basic Vehicle Control Skills Test -On-Road Driving -Practice Questions -Detailed Answer Explanations Disclaimer: CDL(R) is a registered trademark of Commercial Drivers License, which was not involved in the production of, and does not endorse, this product. Each section of the test has a comprehensive review created by Test Prep Books that goes into detail to cover all of the content likely to appear on the CDL test. The Test Prep Books CDL practice test questions are each followed by detailed answer explanations. If you miss a question, it's important that you are able to understand the nature of your mistake and how to avoid making it again in the future. The answer explanations will help you to learn from your mistakes and overcome them. Understanding the latest test-taking strategies is essential to preparing you for what you will expect on the exam. A test taker has to not only understand the material that is being covered on the test, but also must be familiar with the strategies that are necessary to properly utilize the time provided and get through the test without making any avoidable errors. Test Prep Books has drilled down the top test-taking tips for you to know. Anyone planning to take this exam should take advantage of the CDL training review material, practice test questions, and test-taking strategies contained in this Test Prep Books study guide.

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**Popular Science** ,2004-09 Popular Science gives our readers the information and tools to improve their technology and their world. The core belief that Popular Science and our readers share: The future is going to be better, and science and technology are the driving forces that will help make it better.

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

**Commerce Business Daily** ,1999-10

**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.

*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.

*2019 IEEE 9th Annual International Conference on CYBER Technology in Automation, Control, and Intelligent Systems (CYBER)* IEEE Staff,2019-07-29 Cyber Physical Systems Embedded systems integrated sensing, communication, and computational systems chemical, biological, physical diagnostic and implantable systems complex systems mobile intelligent systems micro power grids electric power networks and grids sustainable and distributed energy systems energy scavenging systems cyber technology to protect critical infrastructure Control Automation Adaptive control networked control nonlinear control, multi agent systems co operative control control of energy systems hybrid control intelligent automation intelligent control factory modeling and simulation home, laboratory and service automation automation in energy systems automation in life sciences and healthcare planning, scheduling and coordination biomedical applications Robotics Cooperative robot soft robot industry robot machining robot parallel robot tele robotics human machine interaction perception systems neural con

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.

Review of the 21st Century Truck Partnership National Research Council,Division on Engineering and Physical Sciences,Board on Energy and Environmental Systems,Committee to Review the 21st Century Truck Partnership,2008-10-19 The 21st Century Truck Partnership (21CTP), a cooperative research and development partnership formed by four federal agencies with 15 industrial partners, was launched in the year 2000 with high hopes that it would dramatically advance the technologies

used in trucks and buses, yielding a cleaner, safer, more efficient generation of vehicles. Review of the 21st Century Truck Partnership critically examines and comments on the overall adequacy and balance of the 21CTP. The book reviews how well the program has accomplished its goals, evaluates progress in the program, and makes recommendations to improve the likelihood of the Partnership meeting its goals. Key recommendations of the book include that the 21CTP should be continued, but the future program should be revised and better balanced. A clearer goal setting strategy should be developed, and the goals should be clearly stated in measurable engineering terms and reviewed periodically so as to be based on the available funds.

*Reducing Fuel Consumption and Greenhouse Gas Emissions of Medium- and Heavy-Duty Vehicles, Phase Two* National Academies of Sciences, Engineering, and Medicine, Transportation Research Board, Division on Engineering and Physical Sciences, Board on Energy and Environmental Systems, Committee on Assessment of Technologies and Approaches for Reducing the Fuel Consumption of Medium- and Heavy-Duty Vehicles, Phase Two, 2020-05-15 Medium- and heavy-duty trucks, motor coaches, and transit buses - collectively, medium- and heavy-duty vehicles, or MHDVs - are used in every sector of the economy. The fuel consumption and greenhouse gas emissions of MHDVs have become a focus of legislative and regulatory action in the past few years. This study is a follow-on to the National Research Council's 2010 report, *Technologies and Approaches to Reducing the Fuel Consumption of Medium- and Heavy-Duty Vehicles*. That report provided a series of findings and recommendations on the development of regulations for reducing fuel consumption of MHDVs. On September 15, 2011, NHTSA and EPA finalized joint Phase I rules to establish a comprehensive Heavy-Duty National Program to reduce greenhouse gas emissions and fuel consumption for on-road medium- and heavy-duty vehicles. As NHTSA and EPA began working on a second round of standards, the National Academies issued another report, *Reducing the Fuel Consumption and Greenhouse Gas Emissions of Medium- and Heavy-Duty Vehicles, Phase Two: First Report*, providing recommendations for the Phase II standards. This third and final report focuses on a possible third phase of regulations to be promulgated by these agencies in the next decade.

**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 föreslagna 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.

Los Angeles Magazine ,1999-07 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.

**Road Vehicle Dynamics** Rao V Dukkipati,Jian Pang,Mohamad S Qatu,Gang Sheng,Zuo Shuguang,2008-06-19 This book provides a detailed and well-rounded overview of the dynamics of

road vehicle systems. Readers will come to understand how physical laws, human factor considerations, and design choices come together to affect a vehicle's ride, handling, braking, and acceleration. Following an introduction and general review of dynamics, topics include: analysis of dynamic systems; tire dynamics; ride dynamics; vehicle rollover analysis; handling dynamics; braking; acceleration; and total vehicle dynamics.

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