

# **vehicle\_dynamics\_sim**

Arne Baeyens

**FOSDEM '26**

# The Experience

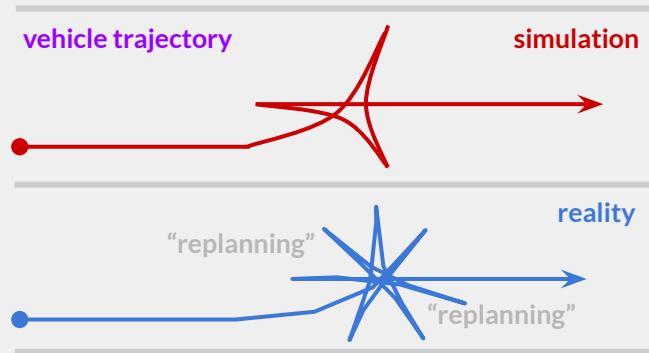


N A V 2

# The Experience



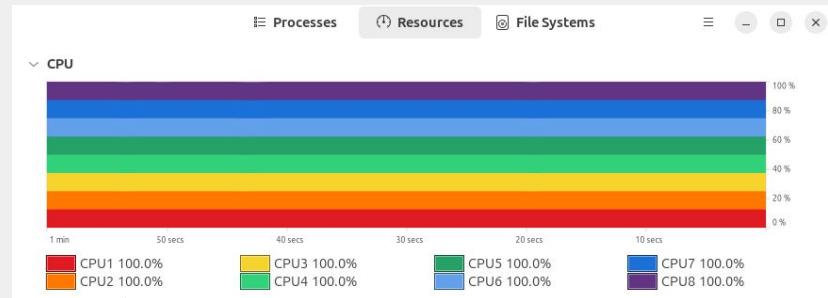
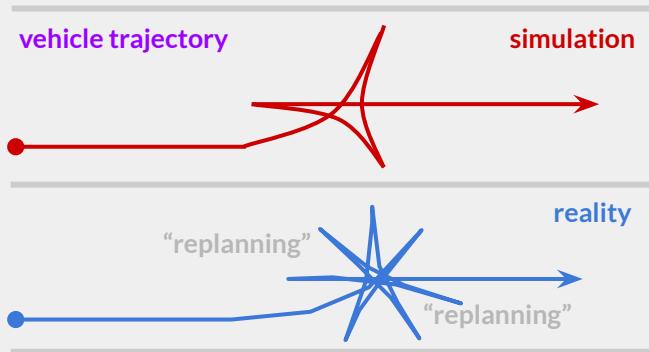
NAV 2



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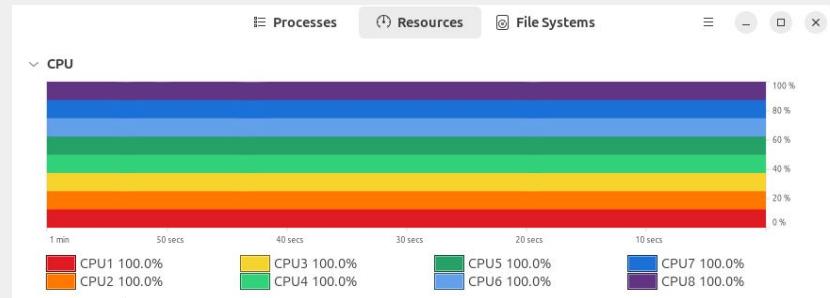
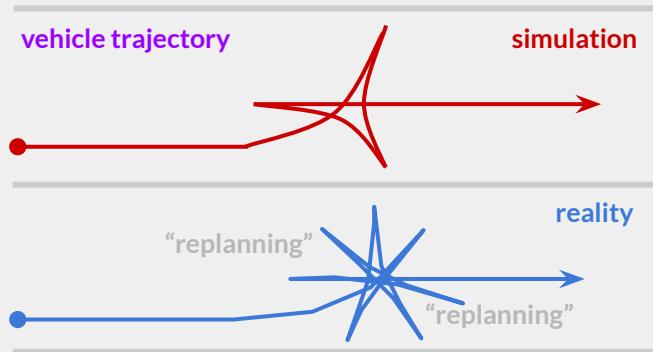
N A V 2



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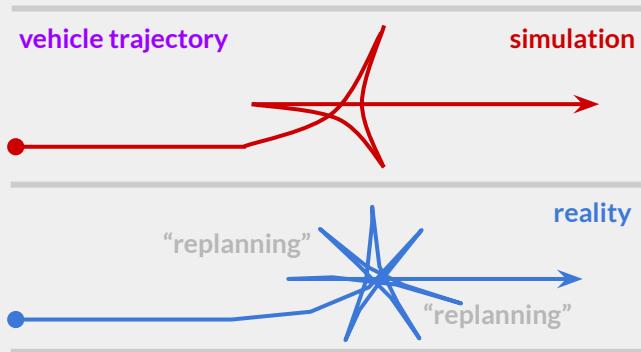
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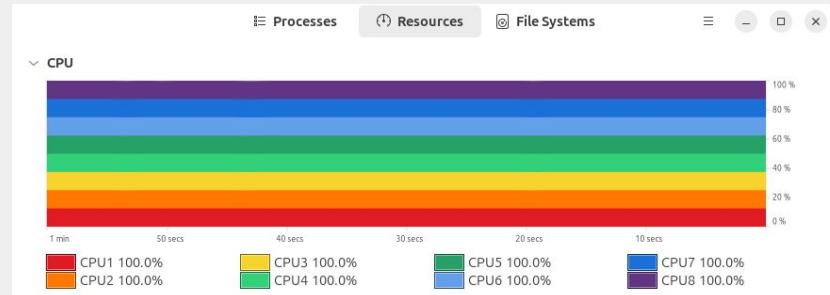
# The Experience



NAV 2



- “Simulation is costly”
- “Simulation slows down development”
- “Simulation doesn’t deliver”



# What can we change ?

Pain points  
and  
Ideas

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**unrealistic dynamics**

**good default vehicle models**

*no custom code required*

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all parameters values  
easily measurable

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laborious set up

- config through ROS 2 params
  - tests easily parametrized
- REP 105 localization simulation
- Run on wall clock
  - no use\_sim\_clock:=true

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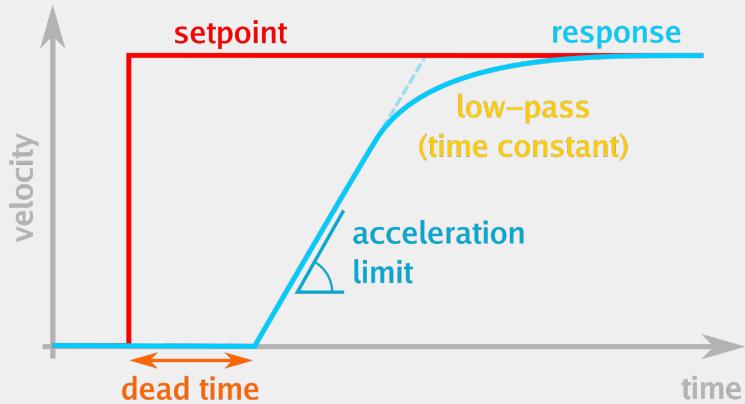
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=> `vehicle_dynamics_sim` <=

# What's in a drive model ?



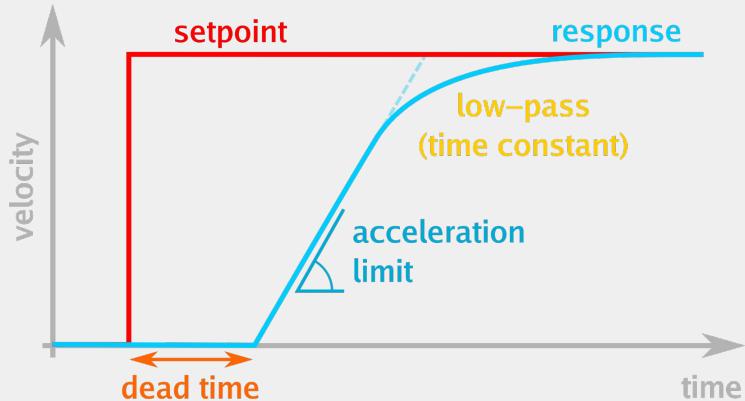
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"Cover key dynamics"

- **dead time**  
finite transmission velocity

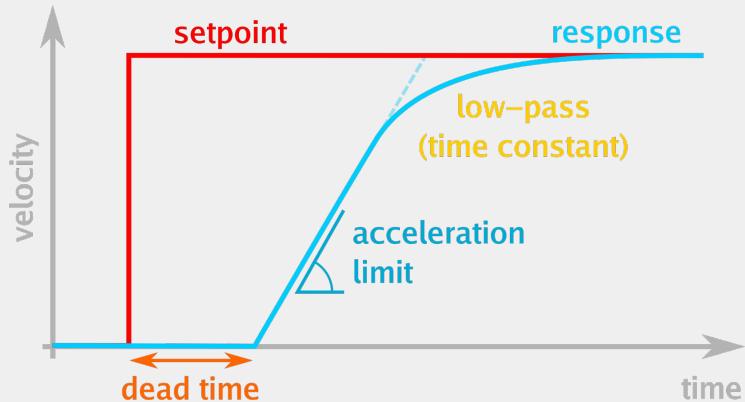
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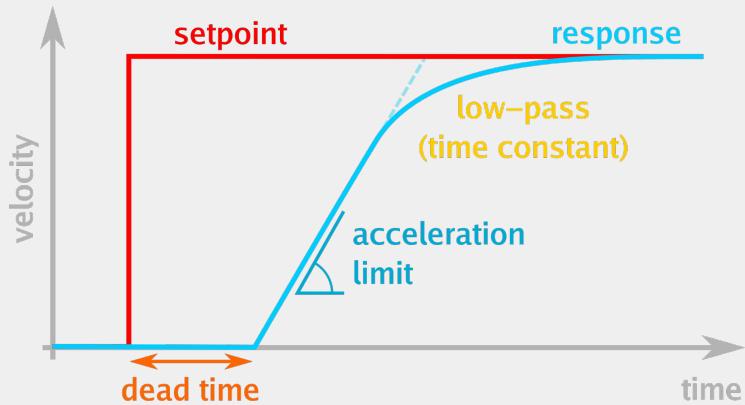
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How to measure **dead time** etc.?

1. Apply step **reference**
2. Measure **response**
3. Read params from graph

# Nav2 demo video

**vehicle\_dynamics\_sim**  
**! thanks !**

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