

TireGround

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Chapter 1

TireGround

A repository for the code developed by Davide Stocco for his thesis.

Department of Industrial Engineering
Master Degree in Mechatronics Engineering

EN: Real-Time Computation of Tire/Road Contact using Tailored Algorithms
IT: Valutazione Real-Time del Contatto Pneumatico/Strada con Algoritmi Dedicati

Academic Year 2019 · 2020

Author: **Davide Stocco**

Supervisor & Co-supervisor: **Prof. Enrico Bertolazzi & Dr.Eng. Matteo Ragni**

MagicFormula tire model usage

1. Load .rdf file.

```
TireGround::RDF::MeshSurface Road(  
    "./file.rdf" // Path to the *.rdf file  
);
```

2. Initialize the MagicFormula tire model.

```
TireGround::Tire* TireSD = new TireGround::MagicFormula(  
    SectionWidth, // [mm]  
    AspectRatio,  // [%]  
    RimDiameter,  // [in]  
    SwitchNumber  // Maximum RoadTriangles in the Tire Shadow (switch to sampling)  
);
```

3. Contact evaluation.

```
bool Out = TireSD->setup( Road,      // Road mesh  
                        TransfMat // 4x4 total transformation matrix  
);
```

4. Data extraction.

```

// Variable initialization (for real numbers)
TireGround::vec3 N;
TireGround::vec3 P;
TireGround::real_type Friction;
TireGround::real_type Rho;
TireGround::real_type RhoDot;
TireGround::real_type RelativeCamber;
TireGround::real_type Area;
TireGround::real_type Volume;

// Data extraction (for real numbers)
TireSD->getNormal(N);
TireSD->getMFpoint(P);
TireSD->getFriction(Friction);
TireSD->getRho(Rho);
TireSD->getRhoDot(PreviousRho, TimeStep, RhoDot);
TireSD->getRelativeCamber(RelativeCamber);
TireSD->getArea(Area);
TireSD->getVolume(Volume);

// Extract data stucture size
TireGround::int_type size = TireSD->getDisksNumber();

// Variable initialization (for vectors)
TireGround::row_vec3 NVec(size);
TireGround::row_vec3 PVec(size);
TireGround::row_vecN FrictionVec(size);
TireGround::row_vecN RhoVec(size);
TireGround::row_vecN RhoDotVec(size);
TireGround::row_vecN RelativeCamberVec(size);
TireGround::row_vecN AreaVec(size);
TireGround::row_vecN VolumeVec(size);

// Data extraction (for vectors)
TireSD->getNormal(NVec);
TireSD->getMFpoint(PVec);
TireSD->getFriction(FrictionVec);
TireSD->getRho(RhoVec);
TireSD->getRhoDot(PreviousRho, TimeStep, RhoDotVec);
TireSD->getRelativeCamber(RelativeCamberVec);
TireSD->getArea(AreaVec);
TireSD->getVolume(VolumeVec);

```

MultiDisk tire model usage

1. Load .rdf file.

```

TireGround::RDF::MeshSurface Road(
    "./file.rdf" // Path to the *.rdf file
);

```

2. Initialize the MultiDisk tire model:

(a) MultiDisk tire without sidewall radius (uniform cylinder).

```

TireGround::Tire* TireMD = new TireGround::MultiDisk(
    SectionWidth, // [mm]
    AspectRatio, // [%]
    RimDiameter, // [in]
    PointsNumber, // Sampling points for each disk
    DisksNumber, // Disks number
    SwitchNumber // Maximum RoadTriangles in the Tire Shadow (switch to sampling)
);

```

(b) MultiDisk tire with sidewall radius (uniform cylinder with filleted sidewall edge).

```

TireGround::Tire* TireMD = new TireGround::MultiDisk(
    SectionWidth, // [mm]
    AspectRatio, // [%]
    RimDiameter, // [in]
    SideRadius, // Sidewall radius [mm]
    PointsNumber, // Sampling points for each disk
    DisksNumber, // Disks number
    SwitchNumber // Maximum RoadTriangles in the Tire Shadow (switch to sampling)
);

```

(c) MultiDisk tire with custom disks radius.

```

TireGround::Tire* TireMD = new TireGround::MultiDisk(
    SectionWidth, // [mm]
    AspectRatio,  // [%]
    RimDiameter,  // [in]
    RadiusVec,    // Disks radius vector [m]
    PointsNumber, // Sampling points for each disk
    SwitchNumber  // Maximum RoadTriangles in the Tire Shadow (switch to sampling)
);

```

3. Contact evaluation.

```

bool Out = TireMD->setup( Road,    // Road mesh
                        TransfMat // 4x4 total transformation matrix
);

```

4. Data extraction for contact point(s).

```

// Variable initialization (for real numbers)
TireGround::vec3 N;
TireGround::vec3 P;
TireGround::real_type Friction;
TireGround::real_type Rho;
TireGround::real_type RhoDot;
TireGround::real_type RelativeCamber;
TireGround::real_type Area;
TireGround::real_type Volume;

// Data extraction (for real numbers)
TireMD->getNormal(N);
TireMD->getMFpoint(P);
TireMD->getFriction(Friction);
TireMD->getRho(Rho);
TireMD->getRhoDot(PreviousRho, TimeStep, RhoDot);
TireMD->getRelativeCamber(RelativeCamber);
TireMD->getArea(Area);
TireMD->getVolume(Volume);

// Extract data stucture size
TireGround::int_type size = TireSD->getDisksNumber();

// Variable initialization (for vectors)
TireGround::row_vec3 NVec(size);
TireGround::row_vec3 PVec(size);
TireGround::row_vecN FrictionVec(size);
TireGround::row_vecN RhoVec(size);
TireGround::row_vecN RhoDotVec(size);
TireGround::row_vecN RelativeCamberVec(size);
TireGround::row_vecN AreaVec(size);
TireGround::row_vecN VolumeVec(size);

// Data extraction (for vectors)
TireMD->getNormal(NVec);
TireMD->getMFpoint(PVec);
TireMD->getFriction(FrictionVec);
TireMD->getRho(RhoVec);
TireMD->getRhoDot(PreviousRho, TimeStep, RhoDotVec);
TireMD->getRelativeCamber(RelativeCamberVec);
TireMD->getArea(AreaVec);
TireMD->getVolume(VolumeVec);

```


Chapter 2

Namespace Index

2.1 Namespace List

Here is a list of all documented namespaces with brief descriptions:

TireGround	
Tire computations routines	11
TireGround::algorithms	
Algorithms for tire computations routine	13
TireGround::RDF	
RDF mesh computations routines	16
TireGround::RDF::algorithms	
Algorithms for RDF mesh computations routine	17

Chapter 3

Hierarchical Index

3.1 Class Hierarchy

This inheritance list is sorted roughly, but not completely, alphabetically:

TireGround::RDF::BBox2D	19
TireGround::Disk	21
TireGround::ETRTO	26
TireGround::RDF::MeshSurface	41
TireGround::ReferenceFrame	62
TireGround::SamplingGrid	65
TireGround::Shadow	68
TicToc	70
TireGround::Tire	71
TireGround::MagicFormula	28
TireGround::MultiDisk	44
TireGround::RDF::Triangle3D	84
TireGround::RDF::TriangleRoad	89

Chapter 4

Class Index

4.1 Class List

Here are the classes, structs, unions and interfaces with brief descriptions:

TireGround::RDF::BBox2D	
2D Bounding Box class	19
TireGround::Disk	
Tire disk	21
TireGround::ETRTO	
Tire ETRTO denomination	26
TireGround::MagicFormula	
Pacejka MagicFormula contact model	28
TireGround::RDF::MeshSurface	
Mesh surface	41
TireGround::MultiDisk	
Multi-disk tire contact model	44
TireGround::ReferenceFrame	
Reference frame	62
TireGround::SamplingGrid	
Patch evaluation precision	65
TireGround::Shadow	
2D shadow (2D bounding box enhancement)	68
TicToc	70
TireGround::Tire	
Base class for Tire models	71
TireGround::RDF::Triangle3D	
3D triangle (pure geometrical description)	84
TireGround::RDF::TriangleRoad	
3D triangles for road representation	89

Chapter 5

Namespace Documentation

5.1 TireGround Namespace Reference

[Tire](#) computations routines.

Namespaces

- [algorithms](#)
Algorithms for tire computations routine.
- [RDF](#)
RDF mesh computations routines.

Classes

- class [Disk](#)
Tire disk.
- class [ETRTO](#)
Tire ETRTO denomination.
- class [MagicFormula](#)
Pacejka MagicFormula contact model.
- class [MultiDisk](#)
Multi-disk tire contact model.
- class [ReferenceFrame](#)
Reference frame.
- class [SamplingGrid](#)
Patch evaluation precision.
- class [Shadow](#)
2D shadow (2D bounding box enhancement)
- class [Tire](#)
Base class for Tire models.

Typedefs

- typedef double [real_type](#)
Real number type.
- typedef int [int_type](#)
Integer number type.
- typedef Eigen::Vector2i [vec2_int](#)
2D vector type of real integer type
- typedef Eigen::Vector2d [vec2](#)
2D vector type of real number type
- typedef Eigen::Vector3d [vec3](#)
3D vector type of real number type
- typedef Eigen::Vector4d [vec4](#)
4D vector type of real number type
- typedef Eigen::Matrix3d [mat3](#)
3x3 matrix type of real number type
- typedef Eigen::Matrix4d [mat4](#)
4x4 matrix type of real number type
- typedef Eigen::Matrix< [real_type](#), 1, Eigen::Dynamic > [row_vecN](#)
Row vector type real number type.
- typedef Eigen::Matrix< [real_type](#), Eigen::Dynamic, 1 > [col_vecN](#)
Column vector type real number type.
- typedef Eigen::Matrix< [real_type](#), Eigen::Dynamic, Eigen::Dynamic > [matN](#)
Matrix type of real number type.
- typedef Eigen::Matrix< [vec2](#), 1, Eigen::Dynamic > [row_vec2](#)
Row vector type of 2D vector.
- typedef Eigen::Matrix< [vec2](#), Eigen::Dynamic, 1 > [col_vec2](#)
Column vector type of 2D vector.
- typedef Eigen::Matrix< [vec2](#), Eigen::Dynamic, Eigen::Dynamic > [mat_vec2](#)
Matrix type of 2D vector.
- typedef Eigen::Matrix< [vec3](#), 1, Eigen::Dynamic > [row_vec3](#)
Row vector type of 3D vector.
- typedef Eigen::Matrix< [vec3](#), Eigen::Dynamic, 1 > [col_vec3](#)
Column vector type of 3D vector.
- typedef Eigen::Matrix< [vec3](#), Eigen::Dynamic, Eigen::Dynamic > [matN_vec3](#)
Matrix type of 3D vector.
- typedef Eigen::Matrix< [mat4](#), 1, Eigen::Dynamic > [row_mat4](#)
Matrix type of 4x4 matrix.
- typedef std::basic_ostream< char > [ostream_type](#)
Output stream type.

Variables

- [real_type](#) const [epsilon](#) = std::numeric_limits<[real_type](#)>::epsilon()
Epsilon type.

5.1.1 Detailed Description

[Tire](#) computations routines.

Typedefs for tire computations routine.

file: [PatchTire.hh](#)

file: [TireGround.hh](#)

5.2 TireGround::algorithms Namespace Reference

Algorithms for tire computations routine.

Functions

- [real_type weightedMean](#) ([row_vecN](#) const &Values, [row_vecN](#) const &Weights)
Calculate arithmetic weighted mean for real numbers.
- [vec3 weightedMean](#) ([row_vec3](#) const &Values, [row_vecN](#) const &Weights)
Calculate arithmetic weighted mean for 3D vectors.
- bool [intersectPointSegment](#) ([vec2](#) const &Point1, [vec2](#) const &Point2, [vec2](#) const &PointQ)
- bool [intersectRayPlane](#) ([vec3](#) const &planeN, [vec3](#) const &planeP, [vec3](#) const &RayPoint, [vec3](#) const &RayDirection, [vec3](#) &IntersectionPt)
Check if a segment hits a plane and find the intersection point.
- void [minmax_XY](#) ([row_vec3](#) const &Points, [vec2](#) &XYmin, [vec2](#) &XYmax)
Calculate mininum and maximum in XY plane for 3D vectors.
- void [minmax_XY](#) ([row_vec2](#) const &Points, [vec2](#) &XYmin, [vec2](#) &XYmax)
Calculate mininum and maximum in XY plane for 2D vectors.
- [real_type trapezoidArea](#) ([real_type](#) const Base2, [real_type](#) const Base1, [real_type](#) const Height)
Calculate area of a trapeziod [m²].

5.2.1 Detailed Description

Algorithms for tire computations routine.

5.2.2 Function Documentation

5.2.2.1 intersectPointSegment()

```
bool TireGround::algorithms::intersectPointSegment (
    vec2 const & Point1,
    vec2 const & Point2,
    vec2 const & PointQ )
```

Check if a point lays inside or outside a line segment

Warning: The point query point must be on the same rect of the line segment!

Parameters

<i>Point1</i>	Line segment point 1
<i>Point2</i>	Line segment point 2
<i>PointQ</i>	Query point

5.2.2.2 intersectRayPlane()

```
bool TireGround::algorithms::intersectRayPlane (
    vec3 const & planeN,
    vec3 const & planeP,
    vec3 const & RayPoint,
    vec3 const & RayDirection,
    vec3 & IntersectionPt )
```

Check if a segment hits a plane and find the intersection point.

Parameters

<i>planeN</i>	Plane normal vector
<i>planeP</i>	Plane known point
<i>RayPoint</i>	Ray point
<i>RayDirection</i>	Ray direction
<i>IntersectionPt</i>	Intersection point

5.2.2.3 minmax_XY() [1/2]

```
void TireGround::algorithms::minmax_XY (
    row_vec3 const & Points,
    vec2 & XYmin,
    vec2 & XYmax )
```

Calculate minimum and maximum in *XY* plane for 3D vectors.

Parameters

<i>Points</i>	3D points vector
<i>XYmin</i>	Minimum (<i>X</i> , <i>Y</i>) values
<i>XYmax</i>	Maximum (<i>X</i> , <i>Y</i>) values

5.2.2.4 minmax_XY() [2/2]

```
void TireGround::algorithms::minmax_XY (
    row_vec2 const & Points,
    vec2 & XYmin,
    vec2 & XYmax )
```

Calculate mininum and maximum in XY plane for 2D vectors.

Parameters

<i>Points</i>	2D points vector
<i>XYmin</i>	Minimum (X , Y) values
<i>XYmax</i>	Maximum (X , Y) values

5.2.2.5 trapezoidArea()

```
real_type TireGround::algorithms::trapezoidArea (
    real_type const Base2,
    real_type const Base1,
    real_type const Height ) [inline]
```

Calculate area of a trapeziod [m^2].

Parameters

<i>Base2</i>	Base 1
<i>Base1</i>	Base 2
<i>Height</i>	Heigth

5.2.2.6 weightedMean() [1/2]

```
real_type TireGround::algorithms::weightedMean (
    row_vecN const & Values,
    row_vecN const & Weights )
```

Calculate arithmetic weighted mean for real numbers.

Parameters

<i>Values</i>	Values (real numbers)
<i>Weights</i>	Weights (real numbers)

5.2.2.7 weightedMean() [2/2]

```
vec3 TireGround::algorithms::weightedMean (
    row_vec3 const & Values,
    row_vecN const & Weights )
```

Calculate arithmetic weighted mean for 3D vectors.

Parameters

<i>Values</i>	Values (3D vectors)
<i>Weights</i>	Weights (real numbers)

5.3 TireGround::RDF Namespace Reference

[RDF](#) mesh computations routines.

Namespaces

- [algorithms](#)
Algorithms for [RDF](#) mesh computations routine.

Classes

- class [BBox2D](#)
2D Bounding Box class
- class [MeshSurface](#)
Mesh surface.
- class [Triangle3D](#)
3D triangle (pure geometrical description)
- class [TriangleRoad](#)
3D triangles for road representation

Typedefs

- typedef std::shared_ptr< [TriangleRoad](#) > [TriangleRoad_ptr](#)
Shared pointer to [TriangleRoad](#) object.
- typedef std::vector< [TriangleRoad_ptr](#) > [TriangleRoad_list](#)
Vector of shared pointers to [TriangleRoad](#) objects.

5.3.1 Detailed Description

[RDF](#) mesh computations routines.

5.4 TireGround::RDF::algorithms Namespace Reference

Algorithms for [RDF](#) mesh computations routine.

Functions

- void [split](#) (std::string const &in, std::vector< std::string > &out, std::string const &token)
Split a string into a string array at a given token.
- std::string [tail](#) (std::string const &in)
Get tail of string after first token and possibly following spaces.
- std::string [firstToken](#) (std::string const &in)
Get first token of string.
- template<typename T >
T const & [getElement](#) (std::vector< T > const &elements, std::string const &index)
Get element at given index position.

5.4.1 Detailed Description

Algorithms for [RDF](#) mesh computations routine.

5.4.2 Function Documentation

5.4.2.1 firstToken()

```
std::string TireGround::RDF::algorithms::firstToken (
    std::string const & in )
```

Get first token of string.

Parameters

<i>in</i>	Input string
-----------	--------------

5.4.2.2 getElement()

```
template<typename T >
T const& TireGround::RDF::algorithms::getElement (
    std::vector< T > const & elements,
    std::string const & index )
```

Get element at given index position.

Parameters

<i>elements</i>	Elements vector
<i>index</i>	Index position

5.4.2.3 split()

```
void TireGround::RDF::algorithms::split (
    std::string const & in,
    std::vector< std::string > & out,
    std::string const & token )
```

Split a string into a string array at a given token.

Parameters

<i>in</i>	Input string
<i>out</i>	Output string vector
<i>token</i>	Token

5.4.2.4 tail()

```
std::string TireGround::RDF::algorithms::tail (
    std::string const & in )
```

Get tail of string after first token and possibly following spaces.

Parameters

<i>in</i>	Input string
-----------	--------------

Chapter 6

Class Documentation

6.1 TireGround::RDF::BBox2D Class Reference

2D Bounding Box class

```
#include <RoadRDF.hh>
```

Public Member Functions

- [BBox2D](#) ()
Default constructor.
- [BBox2D](#) ([vec3](#) const Vertices[3])
Variable set constructor.
- void [setXmin](#) ([real_type](#) const _Xmin)
Set X_{min} shadow domain.
- void [setYmin](#) ([real_type](#) const _Ymin)
Set Y_{min} shadow domain.
- void [setXmax](#) ([real_type](#) const _Xmax)
Set X_{max} shadow domain.
- void [setYmax](#) ([real_type](#) const _Ymax)
Set Y_{max} shadow domain.
- [real_type](#) [getXmin](#) (void) const
Get X_{min} shadow domain.
- [real_type](#) [getYmin](#) (void) const
Get Y_{min} shadow domain.
- [real_type](#) [getXmax](#) (void) const
Get X_{max} shadow domain.
- [real_type](#) [getYmax](#) (void) const
Get Y_{max} shadow domain.
- void [clear](#) (void)
Clear the bounding box domain.
- void [print](#) ([ostream_type](#) &stream) const
Print bounding box domain.
- void [updateBBox2D](#) ([vec3](#) const Vertices[3])
Update the bounding box domain with three input vertices.

6.1.1 Detailed Description

2D Bounding Box class

6.1.2 Constructor & Destructor Documentation

6.1.2.1 BBox2D()

```
TireGround::RDF::BBox2D::BBox2D (
    vec3 const Vertices[3] ) [inline]
```

Variable set constructor.

Parameters

<i>Vertices</i>	Vertices reference vector
-----------------	---------------------------

6.1.3 Member Function Documentation

6.1.3.1 print()

```
void TireGround::RDF::BBox2D::print (
    ostream_type & stream ) const [inline]
```

Print bounding box domain.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

6.1.3.2 updateBBox2D()

```
void TireGround::RDF::BBox2D::updateBBox2D (
    vec3 const Vertices[3] )
```

Update the bounding box domain with three input vertices.

Parameters

<i>Vertices</i>	Vertices reference vector
-----------------	---------------------------

The documentation for this class was generated from the following file:

- include/RoadRDF.hh

6.2 TireGround::Disk Class Reference

[Tire](#) disk.

```
#include <PatchTire.hh>
```

Public Member Functions

- [Disk](#) ([Disk](#) &&)=default
Enable && operator.
- [Disk](#) ()
Default constructor.
- [Disk](#) ([vec2](#) const & _OriginXZ, [real_type](#) _OffsetY, [real_type](#) _Radius)
Variable set constructor.
- void [set](#) ([Disk](#) const &in)
Copy the [Disk](#) object.
- void [setOriginXZ](#) ([vec2](#) const & _OriginXZ)
Set origin on XZ plane.
- [vec2](#) const & [getOriginXZ](#) (void) const
Get origin vector XZ-axes coordinates.
- [vec3](#) [getOriginXYZ](#) (void) const
Get origin vector XYZ-axes coordinates.
- [real_type](#) [getOffsetY](#) (void) const
Get origin Y-axis coordinate.
- [real_type](#) [getRadius](#) (void) const
Get [Disk](#) radius.
- void [contactTriangles](#) ([RDF::TriangleRoad_list](#) const &TriList, [ReferenceFrame](#) const &RF, [vec3](#) &Normal, [real_type](#) &Friction, [real_type](#) &Area) const
- void [contactPlane](#) ([vec3](#) const &Normal, [vec3](#) const &Point, [ReferenceFrame](#) const &RF, [real_type](#) &Area) const
- void [pointOnDisk](#) ([vec3](#) const &Normal, [ReferenceFrame](#) const &RF, [vec3](#) &DiskPoint, [vec3](#) &NormalOnDisk) const
Get the points on [Disk](#) the circumference and on a given plane.
- [real_type](#) [segmentArea](#) ([real_type](#) const Length) const
- bool [isPointInside](#) ([vec2](#) const &Point) const
Check if a point in [Disk](#) reference frame is inside or outside the [Disk](#).
- [real_type](#) [y](#) ([real_type](#) const x) const
Evaluate Y at a query X value on the lower side [Disk](#) circumference.
- [real_type](#) [segmentLength](#) ([vec2](#) const Point1, [vec2](#) const Point2) const

Evaluate a generic segment length given 2 points on the [Disk](#) circumference.

- `int_type intersectSegment (vec2 const &Point1, vec2 const &Point2, vec2 &Intersect1, vec2 &Intersect2) const`
- `bool intersectPlane (vec3 const &Plane_Normal, vec3 const &Plane_Point, vec3 &Line_↔ Direction, vec3 &Line_Point) const`
- `real_type getLineArea (vec2 const &Point1_XZ, vec2 const &Point2_XZ) const`

Get a two points line segment area [m^2] (as output) inside the [Disk](#).

6.2.1 Detailed Description

[Tire](#) disk.

6.2.2 Constructor & Destructor Documentation

6.2.2.1 Disk()

```
TireGround::Disk::Disk (
    vec2 const & _OriginXZ,
    real_type _OffsetY,
    real_type _Radius ) [inline]
```

Variable set constructor.

Parameters

<code>_OriginXZ</code>	(X_0, Z_0) origin coordinate
<code>_OffsetY</code>	Y_0 origin coordinate (offset from center)
<code>_Radius</code>	Radius

6.2.3 Member Function Documentation

6.2.3.1 contactPlane()

```
void TireGround::Disk::contactPlane (
    vec3 const & Normal,
    vec3 const & Point,
    ReferenceFrame const & RF,
    real_type & Area ) const
```

Get the contact area [m^2] inside the single [Disk](#) given a plane in absolute reference frame

Parameters

<i>Normal</i>	Plane normal in absolute reference frame
<i>Point</i>	Plane point in absolute reference frame
<i>RF</i>	Tire ReferenceFrame
<i>Area</i>	Contact area [m^2]

6.2.3.2 contactTriangles()

```
void TireGround::Disk::contactTriangles (
    RDF::TriangleRoad_list const & TriList,
    ReferenceFrame const & RF,
    vec3 & Normal,
    real_type & Friction,
    real_type & Area ) const
```

Get area weighted mean road normal versor, area weighted mean friction and contact area [m^2] inside the single [Disk](#) of segments described by the intersection of triangles on XZ -plane

Parameters

<i>TriList</i>	Shadow / MeshSurface intersected triangles
<i>RF</i>	Tire ReferenceFrame
<i>Normal</i>	Area weighted mean road normal versor
<i>Friction</i>	Area weighted mean contact friction
<i>Area</i>	Contact area [m^2]

6.2.3.3 getLineArea()

```
real_type TireGround::Disk::getLineArea (
    vec2 const & Point1_XZ,
    vec2 const & Point2_XZ ) const
```

Get a two points line segment area [m^2] (as ouput) inside the [Disk](#).

Parameters

<i>Point1_XZ</i>	Point 1 in Disk reference frame
<i>Point2_XZ</i>	Point 2 in Disk reference frame

6.2.3.4 intersectPlane()

```
bool TireGround::Disk::intersectPlane (
    vec3 const & Plane_Normal,
    vec3 const & Plane_Point,
    vec3 & Line_Direction,
    vec3 & Line_Point ) const
```

Check if two plane intersects and find the intersecting rect given two points in [Disk](#) reference frame

Parameters

<i>Plane_Normal</i>	Plane normal vector in Disk reference frame
<i>Plane_Point</i>	Plane known point in Disk reference frame
<i>Line_Direction</i>	Rect direction vector in Disk reference frame
<i>Line_Point</i>	Plane known point in Disk reference frame

6.2.3.5 intersectSegment()

```
int_type TireGround::Disk::intersectSegment (
    vec2 const & Point1,
    vec2 const & Point2,
    vec2 & Intersect1,
    vec2 & Intersect2 ) const
```

Find the intersection points between the [Disk](#) and a two points line segment in [Disk](#) reference frame (output integer gives number of intersection points)

Parameters

<i>Point1</i>	Line segment point 1 in Disk reference frame
<i>Point2</i>	Line segment point 2 in Disk reference frame
<i>Intersect1</i>	Intersection point 1 in Disk reference frame
<i>Intersect2</i>	Intersection point 2 in Disk reference frame

6.2.3.6 isPointInside()

```
bool TireGround::Disk::isPointInside (
    vec2 const & Point ) const
```

Check if a point in [Disk](#) reference frame is inside or outside the [Disk](#).

Parameters

<i>Point</i>	Query point in Disk reference frame
--------------	---

6.2.3.7 segmentArea()

```
real_type TireGround::Disk::segmentArea (
    real_type const Length ) const [inline]
```

Get the contact patch area under the intersection plane in absolute reference frame [m^2]

Parameters

<i>Length</i>	Chord length
---------------	--------------

6.2.3.8 segmentLength()

```
real_type TireGround::Disk::segmentLength (
    vec2 const Point1,
    vec2 const Point2 ) const [inline]
```

Evaluate a generic segment length given 2 points on the [Disk](#) circumference.

Parameters

<i>Point1</i>	Point 1
<i>Point2</i>	Point 2

6.2.3.9 set()

```
void TireGround::Disk::set (
    Disk const & in ) [inline]
```

Copy the [Disk](#) object.

Parameters

<i>in</i>	Disk object to be copied
-----------	--

6.2.3.10 setOriginXZ()

```
void TireGround::Disk::setOriginXZ (
    vec2 const & _OriginXZ ) [inline]
```

Set origin on XZ plane.

Parameters

_OriginXZ	New origin on XZ plane
---------------------------	--------------------------

6.2.3.11 y()

```
real\_type TireGround::Disk::y (
    real\_type const x ) const [inline]
```

Evaluate Y at a query X value on the lower side [Disk](#) circumference.

Parameters

x	Query X value
-----	-----------------

The documentation for this class was generated from the following file:

- include/PatchTire.hh

6.3 TireGround::ETRTO Class Reference

[Tire ETRTO](#) denomination.

```
#include <PatchTire.hh>
```

Public Member Functions

- [ETRTO](#) ()
Default constructor.
- [ETRTO](#) ([real_type](#) _SectionWidth, [real_type](#) _AspectRatio, [real_type](#) _RimDiameter)
Variable set constructor.
- [real_type](#) [getSidewallHeight](#) (void) const
Get sidewall height [m].

- [real_type](#) [getTireDiameter](#) (void) const
Get external tire diameter [m].
- [real_type](#) [getTireRadius](#) (void) const
Get external tire radius [m].
- [real_type](#) [getSectionWidth](#) (void) const
Get section width [m].
- void [print](#) ([ostream_type](#) &stream) const
Display tire data.

6.3.1 Detailed Description

[Tire ETRTO](#) denomination.

6.3.2 Constructor & Destructor Documentation

6.3.2.1 ETRTO()

```
TireGround::ETRTO::ETRTO (
    real\_type _SectionWidth,
    real\_type _AspectRatio,
    real\_type _RimDiameter ) [inline]
```

Variable set constructor.

Parameters

_SectionWidth	Tire section width [m]
_AspectRatio	Tire aspect ratio [%]
_RimDiameter	Rim diameter [in]

6.3.3 Member Function Documentation

6.3.3.1 print()

```
void TireGround::ETRTO::print (
    ostream\_type & stream ) const [inline]
```

Display tire data.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

The documentation for this class was generated from the following file:

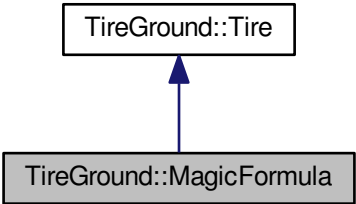
- include/PatchTire.hh

6.4 TireGround::MagicFormula Class Reference

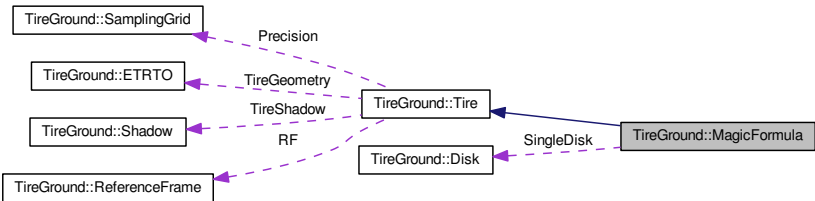
Pacejka [MagicFormula](#) contact model.

```
#include <PatchTire.hh>
```

Inheritance diagram for TireGround::MagicFormula:



Collaboration diagram for TireGround::MagicFormula:



Public Member Functions

- [~MagicFormula](#) ()
Default destructor.
- [MagicFormula](#) ([real_type](#) const SectionWidth, [real_type](#) const AspectRatio, [real_type](#) const RimDiameter, [int_type](#) const SwitchN)
Variable set constructor.
- void [getNormal](#) ([vec3](#) &_Normal) const override
Get contact normal versor.
- void [getNormal](#) ([row_vec3](#) &_Normal) const override
Get contact normal versors vector.
- void [getMFpoint](#) ([vec3](#) &_DiskPoint) const override
Get Magic Formula contact point.
- void [getMFpoint](#) ([row_vec3](#) &_DiskPoint) const override
Get Magic Formula contact point vector.
- void [getFriction](#) ([real_type](#) &_Friction) const override
Get contact point friction.
- void [getFriction](#) ([row_vecN](#) &_Friction) const override
Get contact point friction vector.
- void [getMFpointRF](#) ([mat4](#) &PointRF) const override
Get Magic Formula contact point reference frame with 4x4 transformation matrix.
- void [getMFpointRF](#) ([row_mat4](#) &_MFpointRF) const override
Get Magic Formula contact point reference frame vector with 4x4 transformation matrix.
- void [getRho](#) ([real_type](#) &Rho) const override
- void [getRho](#) ([row_vecN](#) &Rho) const override
- void [getRhoDot](#) ([real_type](#) const &Rho, [real_type](#) const &Time, [real_type](#) &RhoDot) const override
Get contact depth time derivative [m/s].
- void [getRhoDot](#) ([row_vecN](#) const &Rho, [real_type](#) const &Time, [row_vecN](#) &RhoDot) const override
Get contact depth time derivative vector [m/s].
- void [getArea](#) ([real_type](#) &_Area) const override
Get approximated contact area on [Disk](#) plane [m²].
- void [getArea](#) ([row_vecN](#) &_Area) const override
Get approximated contact area vector on [Disk](#) plane [m²].
- void [getVolume](#) ([real_type](#) &_Volume) const override
Get approximated contact volume [m³].
- void [getVolume](#) ([row_vecN](#) &Volume) const override
Get approximated contact volume vector [m³].
- bool [setup](#) ([RDF::MeshSurface](#) &Mesh, [mat4](#) const &TM) override
Update current tire position and find contact parameters.
- void [print](#) ([ostream_type](#) &stream) const override
Print contact parameters.
- void [printETRTOGeometry](#) ([ostream_type](#) &stream) const
Display [Tire ETRTO](#) geometry data.
- [G2lib::AABBtree::PtrAABB](#) const [getAABBtree](#) (void) const
Get total [Tire Shadow](#) [G2Lib::AABBtree](#) (3D projection on ground)
- [G2lib::AABBtree::PtrAABB](#) const [getUpperSideAABBtree](#) (void) const
Get upper side [Tire Shadow](#) [G2Lib::AABBtree](#) (3D projection on ground)

- `G2Lib::AABBtree::PtrAABB` const `getLowerSideAABBtree` (void) const

Get lower side [Tire Shadow](#) `G2Lib::AABBtree` (3D projection on ground)

- void `setReferenceFrame` (`ReferenceFrame` const &_RF)
- `ReferenceFrame` const & `getReferenceFrame` (void) const

Get tire [ReferenceFrame](#) object.

- void `setOrigin` (`vec3` const &Origin)

Set a new tire origin.

- void `setRotationMatrix` (`mat3` const &RotationMatrix)
- void `setTotalTransformationMatrix` (`mat4` const &TM)
- `real_type` `getEulerAngleX` (void) const
- `real_type` `getEulerAngleY` (void) const
- `real_type` `getEulerAngleZ` (void) const
- void `getRelativeCamber` (`real_type` &RelativeCamber) const

Get relative camber angle [rad].

- `int_type` `getDisksNumber` (void) const

Dimension of the contact points data structure (disks number)

Protected Member Functions

- `MagicFormula` (`MagicFormula` const &)=delete

Deleted copy constructor.

- `MagicFormula` const & `operator=` (`MagicFormula` const &)=delete

Deleted copy operator.

- void `evaluateContact` (`RDF::TriangleRoad_list` const &TriList) override

Evaluate contact with [RoadTriangles](#).

- void `fourPointsSampling` (`RDF::TriangleRoad_list` const &TriList, `vec3` &P_star)

Perform triangles sampling on 4 points at $\pm 0.1 \cdot R$ along X and $\pm 0.3 \cdot W$ along Y .

- bool `pointSampling` (`RDF::TriangleRoad_list` const &TriList, `vec3` const &RayOrigin, `vec3` const &RayDirection, `vec3` &SampledPt, `real_type` &TriFriction=quietNaN, `vec3` &TriNormal=vec3_NaN) const

Perform one point sampling (ray-triangle intersection)

Protected Attributes

- `Disk` `SingleDisk`

Single [Disk](#).

- `vec3` `Normal`

Contact normal versor.

- `vec3` `MeshPoint`

Contact point on [Mesh](#) (not for [Magic Formula](#))

- `vec3` `DiskPoint`

Contact point on undeformed [Disk](#) circumference (for [Magic Formula](#))

- `real_type` `Friction`

Contact friction.

- `real_type` `Area`

Contact area [m^2].

- `SamplingGrid` `Precision`

Contact patch evaluating precision.

- [ETRTO TireGeometry](#)
Tire ETRTO denomination.
- [ReferenceFrame RF](#)
ReferenceFrame.
- [Shadow TireShadow](#)
Tire shadow.

6.4.1 Detailed Description

Pacejka [MagicFormula](#) contact model.

6.4.2 Constructor & Destructor Documentation

6.4.2.1 MagicFormula()

```
TireGround::MagicFormula::MagicFormula (
    real_type const SectionWidth,
    real_type const AspectRatio,
    real_type const RimDiameter,
    int_type const SwitchN ) [inline]
```

Variable set constructor.

Parameters

<i>SectionWidth</i>	Tire section width [<i>m</i>]
<i>AspectRatio</i>	Tire aspect ratio [%]
<i>RimDiameter</i>	Rim diameter [<i>in</i>]
<i>SwitchN</i>	Maximum RoadTriangles in the Tire Shadow (switch to sampling)

6.4.3 Member Function Documentation

6.4.3.1 evaluateContact()

```
void TireGround::MagicFormula::evaluateContact (
    RDF::TriangleRoad_list const & TriList ) [override], [protected], [virtual]
```

Evaluate contact with RoadTriangles.

Parameters

<i>TriList</i>	Shadow/MeshSurface intersected triangles
----------------	--

Implements [TireGround::Tire](#).

6.4.3.2 fourPointsSampling()

```
void TireGround::MagicFormula::fourPointsSampling (
    RDF::TriangleRoad_list const & TriList,
    vec3 & P_star ) [protected]
```

Perform triangles sampling on 4 points at $\pm 0.1 \cdot R$ along X and $\pm 0.3 \cdot W$ along Y .

Parameters

<i>TriList</i>	Shadow/MeshSurface intersected triangles
----------------	--

6.4.3.3 getArea() [1/2]

```
void TireGround::MagicFormula::getArea (
    real_type & _Area ) const [inline], [override], [virtual]
```

Get approximated contact area on [Disk](#) plane [m^2].

Parameters

<i>_Area</i>	Contact area [m^2]
--------------	------------------------

Implements [TireGround::Tire](#).

6.4.3.4 getArea() [2/2]

```
void TireGround::MagicFormula::getArea (
    row_vecN & _Area ) const [inline], [override], [virtual]
```

Get approximated contact area vector on [Disk](#) plane [m^2].

Parameters

<code>_Area</code>	Contact area vector [m^2]
--------------------	-------------------------------

Implements [TireGround::Tire](#).

6.4.3.5 getEulerAngleX()

```
real_type TireGround::Tire::getEulerAngleX (
    void ) const [inline], [inherited]
```

Get current Euler angles [rad] for X -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.4.3.6 getEulerAngleY()

```
real_type TireGround::Tire::getEulerAngleY (
    void ) const [inline], [inherited]
```

Get current Euler angles [rad] for Y -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.4.3.7 getEulerAngleZ()

```
real_type TireGround::Tire::getEulerAngleZ (
    void ) const [inline], [inherited]
```

Get current Euler angles [rad] for Z -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.4.3.8 getFriction() [1/2]

```
void TireGround::MagicFormula::getFriction (
    real_type & _Friction ) const [inline], [override], [virtual]
```

Get contact point friction.

Parameters

<code>_Friction</code>	Contact point friction
------------------------	------------------------

Implements [TireGround::Tire](#).

6.4.3.9 getFriction() [2/2]

```
void TireGround::MagicFormula::getFriction (
    row_vecN & _Friction ) const [inline], [override], [virtual]
```

Get contact point friction vector.

Parameters

<i>_Friction</i>	Contact point friction vector
------------------	-------------------------------

Implements [TireGround::Tire](#).

6.4.3.10 getMFpoint() [1/2]

```
void TireGround::MagicFormula::getMFpoint (
    vec3 & _DiskPoint ) const [inline], [override], [virtual]
```

Get Magic Formula contact point.

Parameters

<i>_DiskPoint</i>	Magic Formula contact point
-------------------	-----------------------------

Implements [TireGround::Tire](#).

6.4.3.11 getMFpoint() [2/2]

```
void TireGround::MagicFormula::getMFpoint (
    row_vec3 & _DiskPoint ) const [inline], [override], [virtual]
```

Get Magic Formula contact point vector.

Parameters

<i>_DiskPoint</i>	Contact point vector on Disk
-------------------	--

Implements [TireGround::Tire](#).

6.4.3.12 getMFpointRF() [1/2]

```
void TireGround::MagicFormula::getMFpointRF (
    mat4 & PointRF ) const [override], [virtual]
```

Get Magic Formula contact point reference frame with 4x4 transformation matrix.

Parameters

<i>PointRF</i>	Magic Formula contact point reference frame
----------------	---

Implements [TireGround::Tire](#).

6.4.3.13 getMFpointRF() [2/2]

```
void TireGround::MagicFormula::getMFpointRF (
    row\_mat4 & _MFpointRF ) const [inline], [override], [virtual]
```

Get Magic Formula contact point reference frame vector with 4x4 transformation matrix.

Parameters

<i>_MFpointRF</i>	Magic Formula ontact point reference frames vector
-------------------	--

Implements [TireGround::Tire](#).

6.4.3.14 getNormal() [1/2]

```
void TireGround::MagicFormula::getNormal (
    vec3 & _Normal ) const [inline], [override], [virtual]
```

Get contact normal versor.

Parameters

<i>_Normal</i>	Contact point normal versor
----------------	-----------------------------

Implements [TireGround::Tire](#).

6.4.3.15 `getNormal()` [2/2]

```
void TireGround::MagicFormula::getNormal (
    row_vec3 & _Normal ) const [inline], [override], [virtual]
```

Get contact normal versors vector.

Parameters

<i>_Normal</i>	Contact point normal direction vector
----------------	---------------------------------------

Implements [TireGround::Tire](#).

6.4.3.16 `getRelativeCamber()`

```
void TireGround::Tire::getRelativeCamber (
    real_type & RelativeCamber ) const [inherited]
```

Get relative camber angle [*rad*].

Parameters

<i>RelativeCamber</i>	Relative camber angle
-----------------------	-----------------------

6.4.3.17 `getRho()` [1/2]

```
void TireGround::MagicFormula::getRho (
    real_type & Rho ) const [inline], [override], [virtual]
```

Get contact depth at center point [*m*]

Warning: (if negative the tire does not touch the ground)!

Parameters

<i>Rho</i>	Depth at center point
------------	-----------------------

Implements [TireGround::Tire](#).

6.4.3.18 `getRho()` [2/2]

```
void TireGround::MagicFormula::getRho (
    row_vecN & Rho ) const [inline], [override], [virtual]
```

Get contact depth matrix [m]

Warning: (if negative the tire does not touch the ground)!

Parameters

<i>Rho</i>	Depth matrix
------------	--------------

Implements [TireGround::Tire](#).

6.4.3.19 getRhoDot() [1/2]

```
void TireGround::MagicFormula::getRhoDot (
    real_type const & Rho,
    real_type const & Time,
    real_type & RhoDot ) const [inline], [override], [virtual]
```

Get contact depth time derivative [m/s].

Parameters

<i>Rho</i>	Previous time step Rho [m]
<i>Time</i>	Time step [s]
<i>RhoDot</i>	Penetration derivative [m/s]

Implements [TireGround::Tire](#).

6.4.3.20 getRhoDot() [2/2]

```
void TireGround::MagicFormula::getRhoDot (
    row_vecN const & Rho,
    real_type const & Time,
    row_vecN & RhoDot ) const [inline], [override], [virtual]
```

Get contact depth time derivative vector [m/s].

Parameters

<i>Rho</i>	Previous time step Rho [m]
<i>Time</i>	Time step [s]
<i>RhoDot</i>	Penetration derivative [m/s]

Implements [TireGround::Tire](#).

6.4.3.21 `getVolume()` [1/2]

```
void TireGround::MagicFormula::getVolume (
    real_type & _Volume ) const [inline], [override], [virtual]
```

Get approximated contact volume [m^3].

Parameters

<i>_Volume</i>	Contact volume [m^3]
----------------	--------------------------

Implements [TireGround::Tire](#).

6.4.3.22 `getVolume()` [2/2]

```
void TireGround::MagicFormula::getVolume (
    row_vecN & Volume ) const [inline], [override], [virtual]
```

Get approximated contact volume vector [m^3].

Parameters

<i>Volume</i>	Contact volume vector [m^3]
---------------	---------------------------------

Implements [TireGround::Tire](#).

6.4.3.23 `pointSampling()`

```
bool TireGround::Tire::pointSampling (
    RDF::TriangleRoad_list const & TriList,
    vec3 const & RayOrigin,
    vec3 const & RayDirection,
    vec3 & SampledPt,
    real_type & TriFriction = quietNaN,
    vec3 & TriNormal = vec3_NaN ) const [protected], [inherited]
```

Perform one point sampling (ray-triangle intersection)

Parameters

<i>TriList</i>	Shadow/MeshSurface intersected triangles
----------------	--

Parameters

<i>RayOrigin</i>	Ray origin
<i>RayDirection</i>	Ray direction
<i>SampledPt</i>	Intersection point
<i>TriFriction</i>	Intersected triangle friction
<i>TriNormal</i>	Intersected triangle normal

6.4.3.24 print()

```
void TireGround::MagicFormula::print (
    ostream_type & stream ) const [override], [virtual]
```

Print contact parameters.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

Implements [TireGround::Tire](#).

6.4.3.25 printETRTOGeometry()

```
void TireGround::Tire::printETRTOGeometry (
    ostream_type & stream ) const [inline], [inherited]
```

Display [Tire ETRTO](#) geometry data.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

6.4.3.26 setOrigin()

```
void TireGround::Tire::setOrigin (
    vec3 const & Origin ) [inline], [inherited]
```

Set a new tire origin.

Parameters

<i>Origin</i>	Tire origin
---------------	-----------------------------

6.4.3.27 setReferenceFrame()

```
void TireGround::Tire::setReferenceFrame (
    ReferenceFrame const & _RF ) [inline], [inherited]
```

Copy the tire [ReferenceFrame](#) object

Warning: Rotation matrix must be orthonormal!

Parameters

<i>_RF</i>	ReferenceFrame object to be copied
------------	--

6.4.3.28 setRotationMatrix()

```
void TireGround::Tire::setRotationMatrix (
    mat3 const & RotationMatrix ) [inline], [inherited]
```

Set a new 3x3 rotation matrix

Warning: Rotation matrix must be orthonormal!

Parameters

<i>RotationMatrix</i>	Rotation matrix
-----------------------	-----------------

6.4.3.29 setTotalTransformationMatrix()

```
void TireGround::Tire::setTotalTransformationMatrix (
    mat4 const & TM ) [inline], [inherited]
```

Set 4x4 total transformation matrix

Warning: Rotation matrix must be orthonormal!

Parameters

<i>TM</i>	4x4 total transformation matrix
-----------	---------------------------------

6.4.3.30 setup()

```
bool TireGround::MagicFormula::setup (
    RDF::MeshSurface & Mesh,
    mat4 const & TM ) [override], [virtual]
```

Update current tire position and find contact parameters.

Parameters

<i>Mesh</i>	MeshSurface object (road)
<i>TM</i>	4x4 total transformation matrix

Implements [TireGround::Tire](#).

The documentation for this class was generated from the following file:

- include/PatchTire.hh

6.5 TireGround::RDF::MeshSurface Class Reference

Mesh surface.

```
#include <RoadRDF.hh>
```

Public Member Functions

- [MeshSurface](#) ()
Default set constructor.
- [MeshSurface](#) ([TriangleRoad_list](#) const &_PtrTriangleVec)
Variable set constructor.
- [MeshSurface](#) (std::string const &Path)
Variable set constructor.
- [TriangleRoad_list](#) const & [getTrianglesList](#) (void) const
Get all triangles inside the mesh as a vector.
- [TriangleRoad_ptr](#) const [getTriangle](#) (unsigned i) const
Get i-th TriangleRoad.
- G2lib::AABBtree::PtrAABB const [getAABBPtr](#) (void) const
Get AABBtree object.
- void [printData](#) (std::string const &FileName) const
Print data in file.
- std::vector< G2lib::BBox::PtrBBox > const & [getPtrBBoxList](#) () const
Get the mesh G2lib bounding boxes pointers vector.
- void [set](#) ([MeshSurface](#) const &in)

Copy the [MeshSurface](#) object.

- bool [LoadFile](#) (std::string const &Path)

Load the [RDF](#) model and print information on a file.

- bool [intersectAABBtree](#) (G2lib::AABBtree::PtrAABB const &AABBTreePtr, [RDF::↔
TriangleRoad_list](#) &TrianglesList) const

Intersect the mesh AABB tree with an external AABB tree.

- bool [intersectBBox](#) (std::vector< G2lib::BBox::PtrBBox > const &BBoxPtr, [RDF::↔
TriangleRoad_list](#) &TrianglesList) const

Update the mesh AABBtree with an external G2lib::BBox object pointer vector.

6.5.1 Detailed Description

Mesh surface.

6.5.2 Constructor & Destructor Documentation

6.5.2.1 MeshSurface() [1/2]

```
TireGround::RDF::MeshSurface::MeshSurface (
    TriangleRoad\_list const & _PtrTriangleVec ) [inline]
```

Variable set constructor.

Parameters

_PtrTriangleVec	Road triangles pointer vector list
---------------------------------	------------------------------------

6.5.2.2 MeshSurface() [2/2]

```
TireGround::RDF::MeshSurface::MeshSurface (
    std::string const & Path ) [inline]
```

Variable set constructor.

Parameters

Path	Path to the RDF file
----------------------	--------------------------------------

6.5.3 Member Function Documentation

6.5.3.1 intersectAABBtree()

```
bool TireGround::RDF::MeshSurface::intersectAABBtree (
    G2lib::AABBtree::PtrAABB const & AABBTreePtr,
    RDF::TriangleRoad_list & TrianglesList ) const
```

Intersect the mesh AABB tree with an external AABB tree.

Parameters

<i>AABBTreePtr</i>	External AABBtree object pointer
<i>TrianglesList</i>	Intersected TriangleRoad vector list

6.5.3.2 intersectBBox()

```
bool TireGround::RDF::MeshSurface::intersectBBox (
    std::vector< G2lib::BBox::PtrBBox > const & BBoxPtr,
    RDF::TriangleRoad_list & TrianglesList ) const
```

Update the mesh AABBtree with an external G2lib::BBox object pointer vector.

Parameters

<i>BBoxPtr</i>	External G2lib::BBox object pointer vector
<i>TrianglesList</i>	Intersected TriangleRoad vector list

6.5.3.3 LoadFile()

```
bool TireGround::RDF::MeshSurface::LoadFile (
    std::string const & Path )
```

Load the [RDF](#) model and print information on a file.

Parameters

<i>Path</i>	Path to the RDF file
-------------	--------------------------------------

6.5.3.4 printData()

```
void TireGround::RDF::MeshSurface::printData (
    std::string const & FileName ) const
```

Print data in file.

Parameters

<i>FileName</i>	File name in which print data
-----------------	-------------------------------

6.5.3.5 set()

```
void TireGround::RDF::MeshSurface::set (
    MeshSurface const & in ) [inline]
```

Copy the [MeshSurface](#) object.

Parameters

<i>in</i>	MeshSurface object to be copied
-----------	---

The documentation for this class was generated from the following file:

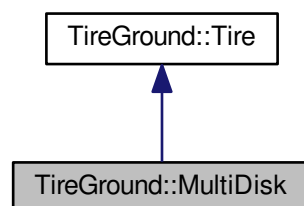
- include/RoadRDF.hh

6.6 TireGround::MultiDisk Class Reference

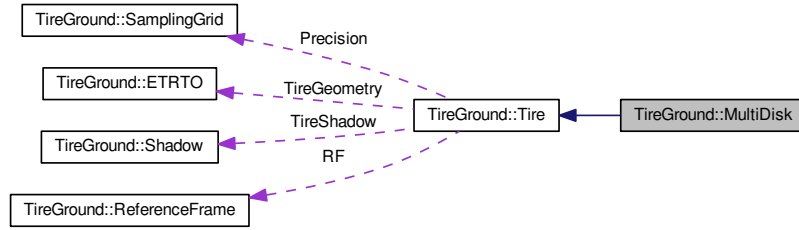
Multi-disk tire contact model.

```
#include <PatchTire.hh>
```

Inheritance diagram for TireGround::MultiDisk:



Collaboration diagram for TireGround::MultiDisk:



Public Member Functions

- [~MultiDisk](#) ()
Default destructor.
- [MultiDisk](#) ([real_type](#) const SectionWidth, [real_type](#) const AspectRatio, [real_type](#) const RimDiameter, [int_type](#) const PointsN, [int_type](#) const DisksN, [int_type](#) const SwitchN)
Variable set constructor.
- [MultiDisk](#) ([real_type](#) const SectionWidth, [real_type](#) const AspectRatio, [real_type](#) const RimDiameter, [real_type](#) const SideRadius, [int_type](#) const PointsN, [int_type](#) const DisksN, [int_type](#) const SwitchN)
Variable set constructor.
- [MultiDisk](#) ([real_type](#) const SectionWidth, [real_type](#) const AspectRatio, [real_type](#) const RimDiameter, [row_vecN](#) const DisksRadius, [int_type](#) const PointsN, [int_type](#) const SwitchN)
Variable set constructor.
- [real_type](#) [getPointstep](#) (void) const
Get grid step on X-axis between sampling points [m].
- [real_type](#) [getDiskStep](#) (void) const
Get step on Y-axis between disks [m].
- void [getNormal](#) ([vec3](#) &_Normal) const override
Get contact normal mean versor.
- void [getDiskOriginXYZ](#) ([row_vec3](#) &Origin) const
Get disks origin (X,Y,Z).
- void [getDiskOriginXYZ](#) ([int_type](#) const i, [vec3](#) &Origin) const
Get i-th Disk origin (X,Y,Z).
- void [setDiskOriginXZ](#) ([row_vec2](#) &Origin)
Set disks origin (X,Y,Z).
- void [setDiskOriginXZ](#) ([int_type](#) const i, [vec2](#) &Origin)
Set i-th Disk origin (X,Y,Z).
- void [getNormal](#) ([row_vec3](#) &_NormalVec) const override
Get contact normal versors vector.
- void [getDiskNormal](#) ([int_type](#) const i, [vec3](#) &_Normal) const
Get i-th Disk contact normal versor.
- void [getMFpoint](#) ([vec3](#) &_DiskPoint) const override
Get Magic Formula contact point.

- void `getMFpoint` (`row_vec3` & `_DiskPointVec`) const override
Get Magic Formula contact points vector.
- void `getDiskMFpoint` (`int_type` const i, `vec3` & `_DiskPoint`) const
Get i-th Disk Magic Formula contact point.
- void `getFriction` (`real_type` & `_Friction`) const override
Get area weighted mean contact friction.
- void `getFriction` (`row_vecN` & `_Friction`) const override
Get contact frictions vector.
- void `getDiskFriction` (`int_type` const i, `real_type` & `_Friction`) const
Get i-th Disk contact friction.
- void `getMFpointRF` (`mat4` & `PointRF`) const override
Get Magic Formula contact point reference frame with 4x4 transformation matrix.
- void `getMFpointRF` (`row_mat4` & `PointRF`) const override
Get Magic Formula contact point reference frames vector with 4x4 transformation matrix.
- void `getDiskMFpointRF` (`int_type` const i, `mat4` & `PointRF`) const
Get Disk Magic Formula contact point reference frame with 4x4 transformation matrix.
- void `getRho` (`real_type` & `Rho`) const override
- void `getRho` (`row_vecN` & `Rho`) const override
- void `getDiskRho` (`int_type` const i, `real_type` & `Rho`) const
- void `getRhoDot` (`real_type` const & `Rho`, `real_type` const & `Time`, `real_type` & `RhoDot`) const override
Get contact depth time derivative [m/s].
- void `getRhoDot` (`row_vecN` const & `Rho`, `real_type` const & `Time`, `row_vecN` & `RhoDot`) const override
Get contact depths derivative vector [m/s].
- void `getDiskRhoDot` (`int_type` const i, `real_type` const & `Rho`, `real_type` const & `Time`, `real_type` & `RhoDot`) const
Get i-th Disk contact depth derivative [m/s].
- void `getArea` (`real_type` & `_Area`) const override
Get approximated mean contact area on Disk plane [m²].
- void `getArea` (`row_vecN` & `_AreaVec`) const override
Get approximated contact areas vector on Disk plane [m²].
- void `getVolume` (`real_type` & `Volume`) const override
Get approximated contact volume [m³].
- void `getVolume` (`row_vecN` & `Volume`) const override
Get approximated contact volumes vector [m³].
- bool `setup` (`RDF::MeshSurface` & `Mesh`, `mat4` const & `TM`) override
Update current tire position and find contact parameters.
- void `print` (`ostream_type` & `stream`) const override
Print contact parameters.
- void `printETRTOGeometry` (`ostream_type` & `stream`) const
Display Tire ETRTO geometry data.
- `G2lib::AABBtree::PtrAABB` const `getAABBtree` (void) const
Get total Tire Shadow G2Lib::AABBtree (3D projection on ground)
- `G2lib::AABBtree::PtrAABB` const `getUpperSideAABBtree` (void) const
Get upper side Tire Shadow G2Lib::AABBtree (3D projection on ground)
- `G2lib::AABBtree::PtrAABB` const `getLowerSideAABBtree` (void) const
Get lower side Tire Shadow G2Lib::AABBtree (3D projection on ground)
- void `setReferenceFrame` (`ReferenceFrame` const & `_RF`)

- [ReferenceFrame](#) const & [getReferenceFrame](#) (void) const
Get tire [ReferenceFrame](#) object.
- void [setOrigin](#) ([vec3](#) const &Origin)
Set a new tire origin.
- void [setRotationMatrix](#) ([mat3](#) const &RotationMatrix)
- void [setTotalTransformationMatrix](#) ([mat4](#) const &TM)
- [real_type](#) [getEulerAngleX](#) (void) const
- [real_type](#) [getEulerAngleY](#) (void) const
- [real_type](#) [getEulerAngleZ](#) (void) const
- void [getRelativeCamber](#) ([real_type](#) &RelativeCamber) const
Get relative camber angle [rad].
- [int_type](#) [getDisksNumber](#) (void) const
Dimension of the contact points data structure (disks number)

Protected Member Functions

- bool [pointSampling](#) ([RDF::TriangleRoad_list](#) const &TriList, [vec3](#) const &RayOrigin, [vec3](#) const &RayDirection, [vec3](#) &SampledPt, [real_type](#) &TriFriction=quietNaN, [vec3](#) &TriNormal=vec3_NaN) const
Perform one point sampling (ray-triangle intersection)

Protected Attributes

- [SamplingGrid Precision](#)
Contact patch evaluating precision.
- [ETRTO TireGeometry](#)
Tire [ETRTO](#) denomination.
- [ReferenceFrame RF](#)
[ReferenceFrame](#).
- [Shadow TireShadow](#)
Tire shadow.

6.6.1 Detailed Description

Multi-disk tire contact model.

6.6.2 Constructor & Destructor Documentation

6.6.2.1 MultiDisk() [1/3]

```
TireGround::MultiDisk::MultiDisk (
    real\_type const SectionWidth,
    real\_type const AspectRatio,
    real\_type const RimDiameter,
    int\_type const PointsN,
    int\_type const DisksN,
    int\_type const SwitchN ) [inline]
```

Variable set constructor.

Parameters

<i>SectionWidth</i>	Tire section width [<i>m</i>]
<i>AspectRatio</i>	Tire aspect ratio [%]
<i>RimDiameter</i>	Rim diameter [<i>in</i>]
<i>PointsN</i>	Sampling points for each Disk (divisions on <i>X</i> -axis)
<i>DisksN</i>	Number of Disks (divisions on <i>Y</i> -axis -1)
<i>SwitchN</i>	Maximum RoadTriangles in the Tire Shadow (switch to sampling)

6.6.2.2 MultiDisk() [2/3]

```
TireGround::MultiDisk::MultiDisk (
    real_type const SectionWidth,
    real_type const AspectRatio,
    real_type const RimDiameter,
    real_type const SideRadius,
    int_type const PointsN,
    int_type const DisksN,
    int_type const SwitchN ) [inline]
```

Variable set constructor.

Parameters

<i>SectionWidth</i>	Tire section width [<i>m</i>]
<i>AspectRatio</i>	Tire aspect ratio [%]
<i>RimDiameter</i>	Rim diameter [<i>in</i>]
<i>SideRadius</i>	Sidewall radius [<i>m</i>]
<i>PointsN</i>	Sampling points for each Disk (divisions on <i>X</i> -axis)
<i>DisksN</i>	Number of Disks (divisions on <i>Y</i> -axis -1)
<i>SwitchN</i>	Maximum RoadTriangles in the Tire Shadow (switch to sampling)

6.6.2.3 MultiDisk() [3/3]

```
TireGround::MultiDisk::MultiDisk (
    real_type const SectionWidth,
    real_type const AspectRatio,
    real_type const RimDiameter,
    row_vecN const DisksRadius,
    int_type const PointsN,
    int_type const SwitchN ) [inline]
```

Variable set constructor.

Parameters

<i>SectionWidth</i>	Tire section width [<i>m</i>]
<i>AspectRatio</i>	Tire aspect ratio [%]
<i>RimDiameter</i>	Rim diameter [<i>in</i>]
<i>DisksRadius</i>	Disks radius vector [<i>m</i>]
<i>PointsN</i>	Sampling points for each Disk (divisions on <i>X</i> -axis)
<i>SwitchN</i>	Maximum RoadTriangles in the Tire Shadow (switch to sampling)

6.6.3 Member Function Documentation

6.6.3.1 `getArea()` [1/2]

```
void TireGround::MultiDisk::getArea (
    real\_type & _Area ) const [inline], [override], [virtual]
```

Get approximated mean contact area on [Disk](#) plane [*m*²].

Parameters

<i>_Area</i>	Contact area [<i>m</i> ²]
--------------	--

Implements [TireGround::Tire](#).

6.6.3.2 `getArea()` [2/2]

```
void TireGround::MultiDisk::getArea (
    row\_vecN & _AreaVec ) const [inline], [override], [virtual]
```

Get approximated contact areas vector on [Disk](#) plane [*m*²].

Parameters

<i>_AreaVec</i>	Contact areas vector [<i>m</i> ²]
-----------------	--

Implements [TireGround::Tire](#).

6.6.3.3 getDiskFriction()

```
void TireGround::MultiDisk::getDiskFriction (
    int_type const i,
    real_type & _Friction ) const [inline]
```

Get *i*-th [Disk](#) contact friction.

Parameters

<i>i</i>	<i>i</i> -th Disk
<i>_Friction</i>	Disk contact friction

6.6.3.4 getDiskMFpoint()

```
void TireGround::MultiDisk::getDiskMFpoint (
    int_type const i,
    vec3 & _DiskPoint ) const [inline]
```

Get *i*-th [Disk](#) Magic Formula contact point.

Parameters

<i>i</i>	<i>i</i> -th Disk
<i>_DiskPoint</i>	Disk Magic Formula contact point

6.6.3.5 getDiskMFpointRF()

```
void TireGround::MultiDisk::getDiskMFpointRF (
    int_type const i,
    mat4 & PointRF ) const [inline]
```

Get [Disk](#) Magic Formula contact point reference frame with 4x4 transformation matrix.

Parameters

<i>i</i>	<i>i</i> -th Disk
<i>PointRF</i>	Magic Formula contact point reference frame

6.6.3.6 getDiskNormal()

```
void TireGround::MultiDisk::getDiskNormal (
    int_type const i,
    vec3 & _Normal ) const [inline]
```

Get i -th [Disk](#) contact normal versor.

Parameters

i	i -th Disk
$_Normal$	Contact normal versor

6.6.3.7 getDiskOriginXYZ() [1/2]

```
void TireGround::MultiDisk::getDiskOriginXYZ (
    row_vec3 & Origin ) const [inline]
```

Get disks origin (X, Y, Z).

Parameters

$Origin$	Disks origin
----------	--------------

6.6.3.8 getDiskOriginXYZ() [2/2]

```
void TireGround::MultiDisk::getDiskOriginXYZ (
    int_type const i,
    vec3 & Origin ) const [inline]
```

Get i -th [Disk](#) origin (X, Y, Z).

Parameters

i	i -th Disk
$Origin$	Disks origin

6.6.3.9 getDiskRho()

```
void TireGround::MultiDisk::getDiskRho (
```

```

    int_type const i,
    real_type & Rho ) const [inline]

```

Get i -th [Disk](#) contact depth [m]

Warning: (if negative the tire does not touch the ground)!

Parameters

i	i -th Disk
Rho	Disk contact depth

6.6.3.10 getDiskRhoDot()

```

void TireGround::MultiDisk::getDiskRhoDot (
    int_type const i,
    real_type const & Rho,
    real_type const & Time,
    real_type & RhoDot ) const [inline]

```

Get i -th [Disk](#) contact depth derivative [m/s].

Parameters

i	i -th Disk
Rho	Previous time step Rho [m]
$Time$	Time step [s]
$RhoDot$	Disk contact depth derivative [m/s]

6.6.3.11 getEulerAngleX()

```

real_type TireGround::Tire::getEulerAngleX (
    void ) const [inline], [inherited]

```

Get current Euler angles [rad] for X -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.6.3.12 getEulerAngleY()

```

real_type TireGround::Tire::getEulerAngleY (
    void ) const [inline], [inherited]

```

Get current Euler angles [rad] for Y -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.6.3.13 getEulerAngleZ()

```
real_type TireGround::Tire::getEulerAngleZ (
    void ) const [inline], [inherited]
```

Get current Euler angles [*rad*] for *Z*-axis
 Warning: Factor as $[R_z][R_x][R_y]!$

6.6.3.14 getFriction() [1/2]

```
void TireGround::MultiDisk::getFriction (
    real_type & _Friction ) const [inline], [override], [virtual]
```

Get area weighted mean contact friction.

Parameters

<i>_Friction</i>	Area weighted mean contact friction
------------------	-------------------------------------

Implements [TireGround::Tire](#).

6.6.3.15 getFriction() [2/2]

```
void TireGround::MultiDisk::getFriction (
    row_vecN & _Friction ) const [inline], [override], [virtual]
```

Get contact frictions vector.

Parameters

<i>_Friction</i>	Contact frictions vector
------------------	--------------------------

Implements [TireGround::Tire](#).

6.6.3.16 getMFpoint() [1/2]

```
void TireGround::MultiDisk::getMFpoint (
    vec3 & _DiskPoint ) const [inline], [override], [virtual]
```

Get Magic Formula contact point.

Parameters

<i>_DiskPoint</i>	Magic Formula contact point
-------------------	-----------------------------

Implements [TireGround::Tire](#).

6.6.3.17 getMFpoint() [2/2]

```
void TireGround::MultiDisk::getMFpoint (
    row_vec3 & _DiskPointVec ) const [inline], [override], [virtual]
```

Get Magic Formula contact points vector.

Parameters

<i>_DiskPointVec</i>	Magic Formula contact points vector
----------------------	-------------------------------------

Implements [TireGround::Tire](#).

6.6.3.18 getMFpointRF() [1/2]

```
void TireGround::MultiDisk::getMFpointRF (
    mat4 & PointRF ) const [inline], [override], [virtual]
```

Get Magic Formula contact point reference frame with 4x4 transformation matrix.

Parameters

<i>PointRF</i>	Magic Formula contact point reference frame
----------------	---

Implements [TireGround::Tire](#).

6.6.3.19 getMFpointRF() [2/2]

```
void TireGround::MultiDisk::getMFpointRF (
    row_mat4 & PointRF ) const [inline], [override], [virtual]
```

Get Magic Formula contact point reference frames vector with 4x4 transformation matrix.

Parameters

<i>PointRF</i>	Magic Formula contact point reference frames vector
----------------	---

Implements [TireGround::Tire](#).

6.6.3.20 getNormal() [1/2]

```
void TireGround::MultiDisk::getNormal (
    vec3 & _Normal ) const [inline], [override], [virtual]
```

Get contact normal mean versor.

Parameters

<i>_Normal</i>	Contact normal mean versor
----------------	----------------------------

Implements [TireGround::Tire](#).

6.6.3.21 getNormal() [2/2]

```
void TireGround::MultiDisk::getNormal (
    row_vec3 & _NormalVec ) const [inline], [override], [virtual]
```

Get contact normal versors vector.

Parameters

<i>_NormalVec</i>	Contact normal versors vector
-------------------	-------------------------------

Implements [TireGround::Tire](#).

6.6.3.22 getRelativeCamber()

```
void TireGround::Tire::getRelativeCamber (
    real_type & RelativeCamber ) const [inherited]
```

Get relative camber angle [*rad*].

Parameters

<i>RelativeCamber</i>	Relative camber angle
-----------------------	-----------------------

6.6.3.23 getRho() [1/2]

```
void TireGround::MultiDisk::getRho (
    real_type & Rho ) const [inline], [override], [virtual]
```

Get contact depth at center point [*m*]

Warning: (if negative the tire does not touch the ground)!

Parameters

<i>Rho</i>	Depth at center point
------------	-----------------------

Implements [TireGround::Tire](#).

6.6.3.24 getRho() [2/2]

```
void TireGround::MultiDisk::getRho (
    row_vecN & Rho ) const [inline], [override], [virtual]
```

Get contact depths vector [*m*]

Warning: (if negative the tire does not touch the ground)!

Parameters

<i>Rho</i>	Contact depths vector
------------	-----------------------

Implements [TireGround::Tire](#).

6.6.3.25 getRhoDot() [1/2]

```
void TireGround::MultiDisk::getRhoDot (
    real_type const & Rho,
    real_type const & Time,
    real_type & RhoDot ) const [inline], [override], [virtual]
```

Get contact depth time derivative [*m/s*].

Parameters

<i>Rho</i>	Previous time step Rho [<i>m</i>]
<i>Time</i>	Time step [<i>s</i>]
<i>RhoDot</i>	Contact depth derivative [<i>m/s</i>]

Implements [TireGround::Tire](#).

6.6.3.26 getRhoDot() [2/2]

```
void TireGround::MultiDisk::getRhoDot (
    row_vecN const & Rho,
    real_type const & Time,
    row_vecN & RhoDot ) const [inline], [override], [virtual]
```

Get contact depths derivative vector [*m/s*].

Parameters

<i>Rho</i>	Previous time step Rho [<i>m</i>]
<i>Time</i>	Time step [<i>s</i>]
<i>RhoDot</i>	Contact depths derivative vector [<i>m/s</i>]

Implements [TireGround::Tire](#).

6.6.3.27 getVolume() [1/2]

```
void TireGround::MultiDisk::getVolume (
    real_type & Volume ) const [inline], [override], [virtual]
```

Get approximated contact volume [*m*³].

Parameters

<i>Volume</i>	Contact volume [<i>m</i> ³]
---------------	--

Implements [TireGround::Tire](#).

6.6.3.28 `getVolume()` [2/2]

```
void TireGround::MultiDisk::getVolume (
    row_vecN & Volume ) const [inline], [override], [virtual]
```

Get approximated contact volumes vector [m^3].

Parameters

<i>Volume</i>	Contact volumes vector [m^3]
---------------	----------------------------------

Implements [TireGround::Tire](#).

6.6.3.29 `pointSampling()`

```
bool TireGround::Tire::pointSampling (
    RDF::TriangleRoad_list const & TriList,
    vec3 const & RayOrigin,
    vec3 const & RayDirection,
    vec3 & SampledPt,
    real_type & TriFriction = quietNaN,
    vec3 & TriNormal = vec3_NaN ) const [protected], [inherited]
```

Perform one point sampling (ray-triangle intersection)

Parameters

<i>TriList</i>	Shadow/MeshSurface intersected triangles
<i>RayOrigin</i>	Ray origin
<i>RayDirection</i>	Ray direction
<i>SampledPt</i>	Intersection point
<i>TriFriction</i>	Intersected triangle friction
<i>TriNormal</i>	Intersected triangle normal

6.6.3.30 `print()`

```
void TireGround::MultiDisk::print (
    ostream_type & stream ) const [override], [virtual]
```

Print contact parameters.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

Implements [TireGround::Tire](#).

6.6.3.31 printETRTOGeometry()

```
void TireGround::Tire::printETRTOGeometry (
    ostream_type & stream ) const [inline], [inherited]
```

Display [Tire ETRTO](#) geometry data.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

6.6.3.32 setDiskOriginXZ() [1/2]

```
void TireGround::MultiDisk::setDiskOriginXZ (
    row_vec2 & Origin ) [inline]
```

Set disks origin (X, Y, Z).

Parameters

<i>Origin</i>	New Disks origin vector
---------------	-------------------------

6.6.3.33 setDiskOriginXZ() [2/2]

```
void TireGround::MultiDisk::setDiskOriginXZ (
    int_type const i,
    vec2 & Origin ) [inline]
```

Set i -th [Disk](#) origin (X, Y, Z).

Parameters

i	i -th Disk
<i>Origin</i>	New Disks origin vector

6.6.3.34 setOrigin()

```
void TireGround::Tire::setOrigin (
    vec3 const & Origin ) [inline], [inherited]
```

Set a new tire origin.

Parameters

<i>Origin</i>	Tire origin
---------------	-----------------------------

6.6.3.35 setReferenceFrame()

```
void TireGround::Tire::setReferenceFrame (
    ReferenceFrame const & _RF ) [inline], [inherited]
```

Copy the tire [ReferenceFrame](#) object

Warning: Rotation matrix must be orthonormal!

Parameters

<i>_RF</i>	ReferenceFrame object to be copied
------------	--

6.6.3.36 setRotationMatrix()

```
void TireGround::Tire::setRotationMatrix (
    mat3 const & RotationMatrix ) [inline], [inherited]
```

Set a new 3x3 rotation matrix

Warning: Rotation matrix must be orthonormal!

Parameters

<i>RotationMatrix</i>	Rotation matrix
-----------------------	-----------------

6.6.3.37 setTotalTransformationMatrix()

```
void TireGround::Tire::setTotalTransformationMatrix (
    mat4 const & TM ) [inline], [inherited]
```

Set 4x4 total transformation matrix

Warning: Rotation matrix must be orthonormal!

Parameters

<i>TM</i>	4x4 total transformation matrix
-----------	---------------------------------

6.6.3.38 setup()

```
bool TireGround::MultiDisk::setup (
    RDF::MeshSurface & Mesh,
    mat4 const & TM ) [override], [virtual]
```

Update current tire position and find contact parameters.

Parameters

<i>Mesh</i>	MeshSurface object (road)
<i>TM</i>	4x4 total transformation matrix

Implements [TireGround::Tire](#).

The documentation for this class was generated from the following file:

- include/PatchTire.hh

6.7 TireGround::ReferenceFrame Class Reference

Reference frame.

```
#include <PatchTire.hh>
```

Public Member Functions

- [ReferenceFrame](#) ()
Default constructor.
- [ReferenceFrame](#) ([vec3](#) const & _Origin, [mat3](#) const & _RotationMatrix)
Variable set constructor.
- bool [isEmpty](#) (void)
Check if [ReferenceFrame](#) object is empty.
- [mat3](#) const & [getRotationMatrix](#) (void) const
Get current 3x3 rotation matrix.
- [mat3](#) [getRotationMatrixInverse](#) (void) const
Get current 3x3 rotation matrix inverse.
- [vec3](#) [getX](#) (void) const
Get current X-axis versor.

- `vec3 getY` (void) const
Get current Y-axis versor.
- `vec3 getZ` (void) const
Get current Z-axis versor.
- `vec3` const & `getOrigin` (void) const
Get origin position.
- void `setOrigin` (`vec3` const & `_Origin`)
Set origin position.
- void `setRotationMatrix` (`mat3` const & `_RotationMatrix`)
Set 3x3 rotation matrix.
- void `setTotalTransformationMatrix` (`mat4` const & `TM`)
Set 4x4 total transformation matrix.
- `mat4` `getTotalTransformationMatrix` (void)
Get 4x4 total transformation matrix.
- void `set` (`ReferenceFrame` const & `in`)
- `real_type` `getEulerAngleX` (void) const
- `real_type` `getEulerAngleY` (void) const
- `real_type` `getEulerAngleZ` (void) const

6.7.1 Detailed Description

Reference frame.

6.7.2 Constructor & Destructor Documentation

6.7.2.1 ReferenceFrame()

```
TireGround::ReferenceFrame::ReferenceFrame (
    vec3 const & _Origin,
    mat3 const & _RotationMatrix ) [inline]
```

Variable set constructor.

Parameters

<code>_Origin</code>	Origin position
<code>_RotationMatrix</code>	3x3 rotation matrix

6.7.3 Member Function Documentation

6.7.3.1 `getEulerAngleX()`

```
real_type TireGround::ReferenceFrame::getEulerAngleX (
    void ) const
```

Get current Euler angles [*rad*] for *X*-axis
 Warning: Factor as $[R_z][R_x][R_y]!$

6.7.3.2 `getEulerAngleY()`

```
real_type TireGround::ReferenceFrame::getEulerAngleY (
    void ) const
```

Get current Euler angles [*rad*] for *Y*-axis
 Warning: Factor as $[R_z][R_x][R_y]!$

6.7.3.3 `getEulerAngleZ()`

```
real_type TireGround::ReferenceFrame::getEulerAngleZ (
    void ) const
```

Get current Euler angles [*rad*] for *Z*-axis
 Warning: Factor as $[R_z][R_x][R_y]!$

6.7.3.4 `set()`

```
void TireGround::ReferenceFrame::set (
    ReferenceFrame const & in ) [inline]
```

Copy the tire [ReferenceFrame](#) object
 Warning: Rotation matrix must be orthonormal!

Parameters

<i>in</i>	ReferenceFrame object to be copied
-----------	--

6.7.3.5 `setOrigin()`

```
void TireGround::ReferenceFrame::setOrigin (
    vec3 const & _Origin ) [inline]
```

Set origin position.

Parameters

<i>_Origin</i>	Origin position
----------------	-----------------

6.7.3.6 setRotationMatrix()

```
void TireGround::ReferenceFrame::setRotationMatrix (
    mat3 const & _RotationMatrix ) [inline]
```

Set 3x3 rotation matrix.

Parameters

<i>_RotationMatrix</i>	3x3 rotation matrix
------------------------	---------------------

6.7.3.7 setTotalTransformationMatrix()

```
void TireGround::ReferenceFrame::setTotalTransformationMatrix (
    mat4 const & TM ) [inline]
```

Set 4x4 total transformation matrix.

Parameters

<i>TM</i>	4x4 total transformation matrix
-----------	---------------------------------

The documentation for this class was generated from the following file:

- include/PatchTire.hh

6.8 TireGround::SamplingGrid Class Reference

Patch evaluation precision.

```
#include <PatchTire.hh>
```

Public Member Functions

- [SamplingGrid](#) ()
Default constructor.
- [SamplingGrid](#) ([int_type](#) _PointsN, [int_type](#) _DisksN)
Variable set constructor.
- [SamplingGrid](#) ([int_type](#) _PointsN, [int_type](#) _DisksN, [int_type](#) _Switch)
Variable set constructor.
- [int_type](#) [getPointsNumber](#) (void) const
Get number of sampling points for each [Disk](#) (divisions on X-axis)
- [int_type](#) [getDisksNumber](#) (void) const
Get number of Disks (divisions on Y-axis -1)
- unsigned [getSwitchNumber](#) (void) const
Get number of maximum RoadTriangles in the [Tire Shadow](#) (switch to sampling)
- void [setSwitchNumber](#) ([int_type](#) const _Switch)
Set number of maximum RoadTriangles in the [Tire Shadow](#) (switch to sampling)
- void [set](#) ([int_type](#) _PointsN, [int_type](#) _DisksN, [int_type](#) _Switch)
Set number of divisions.
- void [set](#) ([SamplingGrid](#) const &in)
Copy the [SamplingGrid](#) object.

6.8.1 Detailed Description

Patch evaluation precision.

6.8.2 Constructor & Destructor Documentation

6.8.2.1 [SamplingGrid](#)() [1/2]

```
TireGround::SamplingGrid::SamplingGrid (
    int\_type _PointsN,
    int\_type _DisksN ) [inline]
```

Variable set constructor.

Parameters

_PointsN	Sampling points for each Disk (divisions on X-axis)
_DisksN	Number of Disks (divisions on Y-axis -1)

6.8.2.2 SamplingGrid() [2/2]

```
TireGround::SamplingGrid::SamplingGrid (
    int_type _PointsN,
    int_type _DisksN,
    int_type _Switch ) [inline]
```

Variable set constructor.

Parameters

<i>_PointsN</i>	Sampling points for each Disk (divisions on <i>X</i> -axis)
<i>_DisksN</i>	Number of Disks (divisions on <i>Y</i> -axis −1)
<i>_Switch</i>	Maximum RoadTriangles in the Tire Shadow (switch to sampling)

6.8.3 Member Function Documentation

6.8.3.1 set() [1/2]

```
void TireGround::SamplingGrid::set (
    int_type _PointsN,
    int_type _DisksN,
    int_type _Switch ) [inline]
```

Set number of divisions.

Parameters

<i>_PointsN</i>	Sampling points for each Disk (divisions on <i>X</i> -axis)
<i>_DisksN</i>	Number of Disks (divisions on <i>Y</i> -axis −1)
<i>_Switch</i>	Maximum RoadTriangles in the Tire Shadow (switch to sampling)

6.8.3.2 set() [2/2]

```
void TireGround::SamplingGrid::set (
    SamplingGrid const & in ) [inline]
```

Copy the [SamplingGrid](#) object.

Parameters

<i>in</i>	SamplingGrid object to be copied
-----------	--

6.8.3.3 setSwitchNumber()

```
void TireGround::SamplingGrid::setSwitchNumber (
    int_type const _Switch ) [inline]
```

Set number of maximum RoadTriangles in the [Tire Shadow](#) (switch to sampling)

Parameters

<code>_Switch</code>	New switch number
----------------------	-------------------

The documentation for this class was generated from the following file:

- include/PatchTire.hh

6.9 TireGround::Shadow Class Reference

2D shadow (2D bounding box enhancement)

```
#include <PatchTire.hh>
```

Public Member Functions

- [Shadow](#) ()
Default constructor.
- [Shadow](#) ([ETRTO](#) const &TireGeometry, [ReferenceFrame](#) const &RF)
- void [update](#) ([ETRTO](#) const &TireGeometry, [ReferenceFrame](#) const &RF)
- G2lib::AABBtree::PtrAABB const [getAABBtree](#) (void) const
Get total [Tire](#) G2Lib::AABBtree (3D projection on ground)
- G2lib::AABBtree::PtrAABB const [getUpperSideAABBtree](#) (void) const
Get upper side [Tire](#) G2Lib::AABBtree (3D projection on ground)
- G2lib::AABBtree::PtrAABB const [getLowerSideAABBtree](#) (void) const
Get lower side [Tire](#) G2Lib::AABBtree (3D projection on ground)

6.9.1 Detailed Description

2D shadow (2D bounding box enhancement)

6.9.2 Constructor & Destructor Documentation

6.9.2.1 Shadow()

```
TireGround::Shadow::Shadow (
    ETRTO const & TireGeometry,
    ReferenceFrame const & RF ) [inline]
```

Variable set constructor

Warning: Rotation matrix must be orthonormal!

Parameters

<i>TireGeometry</i>	Tire ETRTO denomination
<i>RF</i>	Tire ReferenceFrame

6.9.3 Member Function Documentation

6.9.3.1 update()

```
void TireGround::Shadow::update (
    ETRTO const & TireGeometry,
    ReferenceFrame const & RF )
```

Update the 2D tire shadow domain

Warning: Rotation matrix must be orthonormal!

Parameters

<i>TireGeometry</i>	Tire ETRTO denomination
<i>RF</i>	Tire ReferenceFrame

The documentation for this class was generated from the following file:

- `include/PatchTire.hh`

6.10 TicToc Class Reference

Public Member Functions

- void **tic** ()
- void **toc** ()
- `real_type` **elapsed_s** () const
- `real_type` **elapsed_ms** () const

The documentation for this class was generated from the following file:

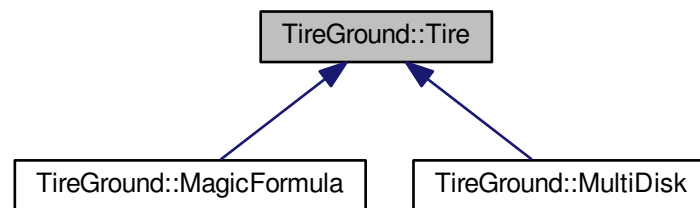
- `include/TicToc.hh`

6.11 TireGround::Tire Class Reference

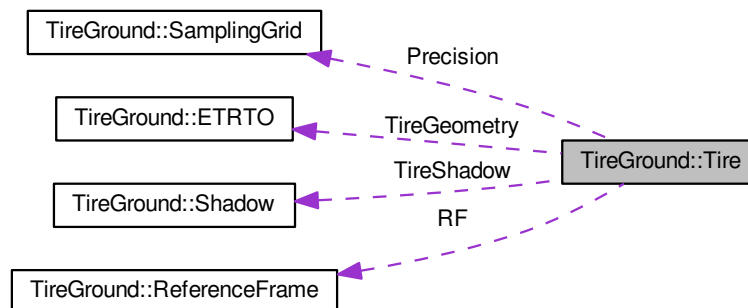
Base class for [Tire](#) models.

```
#include <PatchTire.hh>
```

Inheritance diagram for TireGround::Tire:



Collaboration diagram for TireGround::Tire:



Public Member Functions

- `~Tire()`
Default destructor.
- `Tire(real_type const SectionWidth, real_type const AspectRatio, real_type const RimDiameter, int_type const PointsN, int_type const DisksN)`
Variable set constructor.
- `void printETRTOGeometry(ostream_type &stream) const`
Display Tire ETRTO geometry data.
- `G2lib::AABBtree::PtrAABB const getAABBtree(void) const`

- *Get total [Tire Shadow](#) [G2Lib::AABBtree](#) (3D projection on ground)*
 - [G2lib::AABBtree::PtrAABB](#) const [getUpperSideAABBtree](#) (void) const
- *Get upper side [Tire Shadow](#) [G2Lib::AABBtree](#) (3D projection on ground)*
 - [G2lib::AABBtree::PtrAABB](#) const [getLowerSideAABBtree](#) (void) const
- *Get lower side [Tire Shadow](#) [G2Lib::AABBtree](#) (3D projection on ground)*
 - void [setReferenceFrame](#) ([ReferenceFrame](#) const &_RF)
 - [ReferenceFrame](#) const & [getReferenceFrame](#) (void) const
- *Get tire [ReferenceFrame](#) object.*
 - void [setOrigin](#) ([vec3](#) const &Origin)
- *Set a new tire origin.*
 - void [setRotationMatrix](#) ([mat3](#) const &RotationMatrix)
 - void [setTotalTransformationMatrix](#) ([mat4](#) const &TM)
 - [real_type](#) [getEulerAngleX](#) (void) const
 - [real_type](#) [getEulerAngleY](#) (void) const
 - [real_type](#) [getEulerAngleZ](#) (void) const
 - void [getRelativeCamber](#) ([real_type](#) &RelativeCamber) const
- *Get relative camber angle [rad].*
 - [int_type](#) [getDisksNumber](#) (void) const
- *Dimension of the contact points data structure (disks number)*
 - virtual void [getRho](#) ([real_type](#) &Rho) const =0
 - virtual void [getRho](#) ([row_vecN](#) &Rho) const =0
 - virtual void [getRhoDot](#) ([real_type](#) const &Rho, [real_type](#) const &Time, [real_type](#) &Rho↔
Dot) const =0
- *Get contact depth time derivative [m/s].*
 - virtual void [getRhoDot](#) ([row_vecN](#) const &Rho, [real_type](#) const &Time, [row_vecN](#) &Rho↔
Dot) const =0
- *Get contact depth time derivative vector [m/s].*
 - virtual void [getNormal](#) ([vec3](#) &Normal) const =0
- *Get contact normal versor.*
 - virtual void [getNormal](#) ([row_vec3](#) &Normal) const =0
- *Get contact normal versors vector.*
 - virtual void [getMFpoint](#) ([vec3](#) &Point) const =0
- *Get Magic Formula contact point.*
 - virtual void [getMFpoint](#) ([row_vec3](#) &Point) const =0
- *Get Magic Formula contact point vector.*
 - virtual void [getFriction](#) ([real_type](#) &Friction) const =0
- *Get contact point friction.*
 - virtual void [getFriction](#) ([row_vecN](#) &Friction) const =0
- *Get contact frictions vector.*
 - virtual void [getMFpointRF](#) ([mat4](#) &PointRF) const =0
- *Get Magic Formula contact point reference frame with 4x4 transformation matrix.*
 - virtual void [getMFpointRF](#) ([row_mat4](#) &PointRF) const =0
- *Get Magic Formula contact point reference frame vector with 4x4 transformation matrix.*
 - virtual void [getArea](#) ([real_type](#) &_Area) const =0
- *Get approximated contact area on [Disk](#) plane [m²].*
 - virtual void [getArea](#) ([row_vecN](#) &Area) const =0
- *Get approximated contact areas vector on [Disk](#) plane [m²].*
 - virtual void [getVolume](#) ([real_type](#) &Volume) const =0
- *Get approximated contact volume [m³].*

- virtual void `getVolume` (`row_vecN` & `_Volume`) const =0
Get approximated contact volume [m³].
- virtual void `evaluateContact` (`RDF::TriangleRoad_list` const & `TriList`)=0
Evaluate contact with RoadTriangles.
- virtual bool `setup` (`RDF::MeshSurface` & `Mesh`, `mat4` const & `TM`)=0
Update current tire position and find contact parameters.
- virtual void `print` (`ostream_type` & `stream`) const =0
Print contact parameters.

Protected Member Functions

- `Tire` (`Tire` const &)=delete
Deleted copy constructor.
- `Tire` const & `operator=` (`Tire` const &)=delete
Deleted copy operator.
- bool `pointSampling` (`RDF::TriangleRoad_list` const & `TriList`, `vec3` const & `RayOrigin`, `vec3` const & `RayDirection`, `vec3` & `SampledPt`, `real_type` & `TriFriction`=quietNaN, `vec3` & `TriNormal`=`vec3_NaN`) const
Perform one point sampling (ray-triangle intersection)

Protected Attributes

- `SamplingGrid Precision`
Contact patch evaluating precision.
- `ETRTO TireGeometry`
Tire ETRTO denomination.
- `ReferenceFrame RF`
ReferenceFrame.
- `Shadow TireShadow`
Tire shadow.

6.11.1 Detailed Description

Base class for `Tire` models.

6.11.2 Constructor & Destructor Documentation

6.11.2.1 `Tire()`

```
TireGround::Tire::Tire (
    real_type const SectionWidth,
    real_type const AspectRatio,
    real_type const RimDiameter,
    int_type const PointsN,
    int_type const DisksN ) [inline]
```

Variable set constructor.

Parameters

<i>SectionWidth</i>	Tire section width [<i>m</i>]
<i>AspectRatio</i>	Tire aspect ratio [%]
<i>RimDiameter</i>	Rim diameter [<i>in</i>]
<i>PointsN</i>	Sampling points for each Disk (divisions on <i>X</i> -axis)
<i>DisksN</i>	Number of Disks (divisions on <i>Y</i> -axis -1)

6.11.3 Member Function Documentation

6.11.3.1 evaluateContact()

```
virtual void TireGround::Tire::evaluateContact (
    RDF::TriangleRoad\_list const & TriList ) [pure virtual]
```

Evaluate contact with RoadTriangles.

Parameters

<i>TriList</i>	Shadow/MeshSurface intersected triangles
----------------	--

Implemented in [TireGround::MagicFormula](#).

6.11.3.2 getArea() [1/2]

```
virtual void TireGround::Tire::getArea (
    real\_type & _Area ) const [pure virtual]
```

Get approximated contact area on [Disk](#) plane [m^2].

Parameters

<i>_Area</i>	Contact area [m^2]
--------------	------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.3 getArea() [2/2]

```
virtual void TireGround::Tire::getArea (
    row_vecN & Area ) const [pure virtual]
```

Get approximated contact areas vector on [Disk](#) plane [m^2].

Parameters

<i>Area</i>	Contact areas vector [m^2]
-------------	--------------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.4 getEulerAngleX()

```
real_type TireGround::Tire::getEulerAngleX (
    void ) const [inline]
```

Get current Euler angles [rad] for X -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.11.3.5 getEulerAngleY()

```
real_type TireGround::Tire::getEulerAngleY (
    void ) const [inline]
```

Get current Euler angles [rad] for Y -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.11.3.6 getEulerAngleZ()

```
real_type TireGround::Tire::getEulerAngleZ (
    void ) const [inline]
```

Get current Euler angles [rad] for Z -axis

Warning: Factor as $[R_z][R_x][R_y]!$

6.11.3.7 getFriction() [1/2]

```
virtual void TireGround::Tire::getFriction (
    real_type & Friction ) const [pure virtual]
```

Get contact point friction.

Parameters

<i>Friction</i>	Contact point friction
-----------------	------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.8 getFriction() [2/2]

```
virtual void TireGround::Tire::getFriction (
    row_vecN & Friction ) const [pure virtual]
```

Get contact frictions vector.

Parameters

<i>Friction</i>	Contact frictions vector
-----------------	--------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.9 getMFpoint() [1/2]

```
virtual void TireGround::Tire::getMFpoint (
    vec3 & Point ) const [pure virtual]
```

Get Magic Formula contact point.

Parameters

<i>Point</i>	Magic Formula contact point
--------------	-----------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.10 getMFpoint() [2/2]

```
virtual void TireGround::Tire::getMFpoint (
    row_vec3 & Point ) const [pure virtual]
```

Get Magic Formula contact point vector.

Parameters

<i>Point</i>	Magic Formula Contact point vector
--------------	------------------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.11 getMFpointRF() [1/2]

```
virtual void TireGround::Tire::getMFpointRF (
    mat4 & PointRF ) const [pure virtual]
```

Get Magic Formula contact point reference frame with 4x4 transformation matrix.

Parameters

<i>PointRF</i>	Magic Formula contact point reference frame
----------------	---

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.12 getMFpointRF() [2/2]

```
virtual void TireGround::Tire::getMFpointRF (
    row_mat4 & PointRF ) const [pure virtual]
```

Get Magic Formula contact point reference frame vector with 4x4 transformation matrix.

Parameters

<i>PointRF</i>	Magic Formula ontact point reference frames vector
----------------	--

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.13 getNormal() [1/2]

```
virtual void TireGround::Tire::getNormal (
    vec3 & Normal ) const [pure virtual]
```

Get contact normal versor.

Parameters

<i>Normal</i>	Contact point normal direction
---------------	--------------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.14 getNormal() [2/2]

```
virtual void TireGround::Tire::getNormal (
    row_vec3 & Normal ) const [pure virtual]
```

Get contact normal versors vector.

Parameters

<i>Normal</i>	Contact point normal direction vector
---------------	---------------------------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.15 getRelativeCamber()

```
void TireGround::Tire::getRelativeCamber (
    real_type & RelativeCamber ) const
```

Get relative camber angle [*rad*].

Parameters

<i>RelativeCamber</i>	Relative camber angle
-----------------------	-----------------------

6.11.3.16 getRho() [1/2]

```
virtual void TireGround::Tire::getRho (
    real_type & Rho ) const [pure virtual]
```

Get contact depth at center point [*m*]

Warning: (if negative the tire does not touch the ground)!

Parameters

<i>Rho</i>	Depth at center point
------------	-----------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.17 getRho() [2/2]

```
virtual void TireGround::Tire::getRho (
    row_vecN & Rho ) const [pure virtual]
```

Get contact depth vector [m]

Warning: (if negative the tire does not touch the ground)!

Parameters

<i>Rho</i>	Depth vector [m]
------------	----------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.18 getRhoDot() [1/2]

```
virtual void TireGround::Tire::getRhoDot (
    real_type const & Rho,
    real_type const & Time,
    real_type & RhoDot ) const [pure virtual]
```

Get contact depth time derivative [m/s].

Parameters

<i>Rho</i>	Previous time step Rho [m]
<i>Time</i>	Time step [s]
<i>RhoDot</i>	Penetration derivative [m/s]

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.19 getRhoDot() [2/2]

```
virtual void TireGround::Tire::getRhoDot (
    row_vecN const & Rho,
    real_type const & Time,
    row_vecN & RhoDot ) const [pure virtual]
```

Get contact depth time derivative vector [m/s].

Parameters

<i>Rho</i>	Previous time step Rho [<i>m</i>]
<i>Time</i>	Time step [<i>s</i>]
<i>RhoDot</i>	Penetration derivative [<i>m/s</i>]

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.20 getVolume() [1/2]

```
virtual void TireGround::Tire::getVolume (
    real\_type & Volume ) const [pure virtual]
```

Get approximated contact volume [*m*³].

Parameters

<i>Volume</i>	Contact volume [<i>m</i> ³]
---------------	--

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.21 getVolume() [2/2]

```
virtual void TireGround::Tire::getVolume (
    row\_vecN & _Volume ) const [pure virtual]
```

Get approximated contact volume [*m*³].

Parameters

<i>_Volume</i>	Contact volume vector [<i>m</i> ³]
----------------	---

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.22 pointSampling()

```
bool TireGround::Tire::pointSampling (
    RDF::TriangleRoad\_list const & TriList,
    vec3 const & RayOrigin,
```

```

    vec3 const & RayDirection,
    vec3 & SampledPt,
    real_type & TriFriction = quietNaN,
    vec3 & TriNormal = vec3_NaN ) const [protected]

```

Perform one point sampling (ray-triangle intersection)

Parameters

<i>TriList</i>	Shadow/MeshSurface intersected triangles
<i>RayOrigin</i>	Ray origin
<i>RayDirection</i>	Ray direction
<i>SampledPt</i>	Intersection point
<i>TriFriction</i>	Intersected triangle friction
<i>TriNormal</i>	Intersected triangle normal

6.11.3.23 print()

```

virtual void TireGround::Tire::print (
    ostream_type & stream ) const [pure virtual]

```

Print contact parameters.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

6.11.3.24 printETRTOGeometry()

```

void TireGround::Tire::printETRTOGeometry (
    ostream_type & stream ) const [inline]

```

Display [Tire ETRTO](#) geometry data.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

6.11.3.25 setOrigin()

```
void TireGround::Tire::setOrigin (
    vec3 const & Origin ) [inline]
```

Set a new tire origin.

Parameters

<i>Origin</i>	Tire origin
---------------	-----------------------------

6.11.3.26 setReferenceFrame()

```
void TireGround::Tire::setReferenceFrame (
    ReferenceFrame const & _RF ) [inline]
```

Copy the tire [ReferenceFrame](#) object

Warning: Rotation matrix must be orthonormal!

Parameters

<i>_RF</i>	ReferenceFrame object to be copied
------------	--

6.11.3.27 setRotationMatrix()

```
void TireGround::Tire::setRotationMatrix (
    mat3 const & RotationMatrix ) [inline]
```

Set a new 3x3 rotation matrix

Warning: Rotation matrix must be orthonormal!

Parameters

<i>RotationMatrix</i>	Rotation matrix
-----------------------	-----------------

6.11.3.28 setTotalTransformationMatrix()

```
void TireGround::Tire::setTotalTransformationMatrix (
    mat4 const & TM ) [inline]
```

Set 4x4 total transformation matrix

Warning: Rotation matrix must be orthonormal!

Parameters

<i>TM</i>	4x4 total transformation matrix
-----------	---------------------------------

6.11.3.29 setup()

```
virtual bool TireGround::Tire::setup (
    RDF::MeshSurface & Mesh,
    mat4 const & TM ) [pure virtual]
```

Update current tire position and find contact parameters.

Parameters

<i>Mesh</i>	MeshSurface object (road)
<i>TM</i>	4x4 total transformation matrix

Implemented in [TireGround::MultiDisk](#), and [TireGround::MagicFormula](#).

The documentation for this class was generated from the following file:

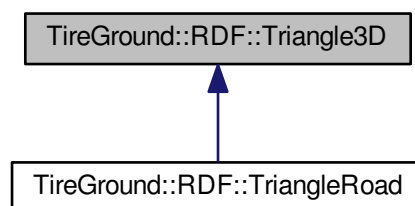
- include/PatchTire.hh

6.12 TireGround::RDF::Triangle3D Class Reference

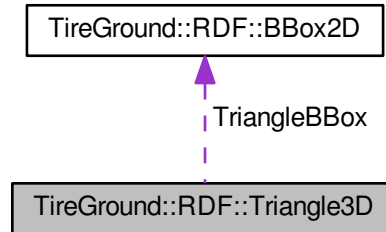
3D triangle (pure geometrical description)

```
#include <RoadRDF.hh>
```

Inheritance diagram for TireGround::RDF::Triangle3D:



Collaboration diagram for TireGround::RDF::Triangle3D:



Public Member Functions

- [Triangle3D](#) ()
Variable set constructor.
- [Triangle3D](#) ([vec3](#) const _ Vertices[3])
Variable set constructor.
- void [setVertices](#) ([vec3](#) const _ Vertices[3])
Set new vertices and update bounding box domain.
- void [setVertices](#) ([vec3](#) const &Vertex0, [vec3](#) const &Vertex1, [vec3](#) const &Vertex2)
Set new vertices then update bounding box domain and normal versor.
- [vec3](#) const & [getNormal](#) (void) const
Get normal versor.
- [vec3](#) const & [getVertex](#) (unsigned i) const
Get i-th vertex.
- [BBox2D](#) const & [getBBox](#) (void) const
Get [Triangle3D](#) bonding box [BBox2D](#).
- void [print](#) (ostream_type &stream) const
Print vertices data.
- bool [intersectRay](#) ([vec3](#) const &RayOrigin, [vec3](#) const &RayDirection, [vec3](#) &IntPt) const
- int_type [intersectEdgePlane](#) ([vec3](#) const &PlaneN, [vec3](#) const &PlaneP, int_type const Edge, [vec3](#) &IntPt1, [vec3](#) &IntPt2) const
- bool [intersectPlane](#) ([vec3](#) const &PlaneN, [vec3](#) const &PlaneP, std::vector< [vec3](#) > &IntPts) const

Protected Member Functions

- [Triangle3D](#) ([Triangle3D](#) const &)=delete
Deleted copy constructor.
- [Triangle3D](#) & [operator=](#) ([Triangle3D](#) const &)=delete
Deleted copy operator.

Protected Attributes

- [vec3 Vertices](#) [3]
Vertices reference vector.
- [vec3 Normal](#)
Triangle normal versor.
- [BBox2D TriangleBBox](#)
Triangle 2D bounding box (XY plane)

6.12.1 Detailed Description

3D triangle (pure geometrical description)

6.12.2 Constructor & Destructor Documentation

6.12.2.1 Triangle3D()

```
TireGround::RDF::Triangle3D::Triangle3D (
    vec3 const _Vertices[3] ) [inline]
```

Variable set constructor.

Parameters

<code>_Vertices</code>	Vertices reference vector
------------------------	---------------------------

6.12.3 Member Function Documentation

6.12.3.1 intersectEdgePlane()

```
int\_type TireGround::RDF::Triangle3D::intersectEdgePlane (
    vec3 const & PlaneN,
    vec3 const & PlaneP,
    int\_type const Edge,
    vec3 & IntPt1,
    vec3 & IntPt2 ) const
```

Check if an edge of the [Triangle3D](#) object hits a and find the intersection point

Parameters

<i>PlaneN</i>	Plane normal vector
<i>PlaneP</i>	Plane known point
<i>Edge</i>	Triangle edge number (0:2)
<i>IntPt1</i>	Intersection point 1
<i>IntPt2</i>	Intersection point 2

6.12.3.2 intersectPlane()

```
bool TireGround::RDF::Triangle3D::intersectPlane (
    vec3 const & PlaneN,
    vec3 const & PlaneP,
    std::vector< vec3 > & IntPts ) const
```

Check if a plane intersects a [Triangle3D](#) object and find the intersection points

Parameters

<i>PlaneN</i>	Plane normal vector
<i>PlaneP</i>	Plane known point
<i>IntPts</i>	Intersection points

6.12.3.3 intersectRay()

```
bool TireGround::RDF::Triangle3D::intersectRay (
    vec3 const & RayOrigin,
    vec3 const & RayDirection,
    vec3 & IntPt ) const
```

Check if a ray hits a [Triangle3D](#) object through Möller-Trumbore intersection algorithm

Parameters

<i>RayOrigin</i>	Ray origin position
<i>RayDirection</i>	Ray direction vector
<i>IntPt</i>	Intersection point

6.12.3.4 print()

```
void TireGround::RDF::Triangle3D::print (
    ostream_type & stream ) const [inline]
```

Print vertices data.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

6.12.3.5 setVertices() [1/2]

```
void TireGround::RDF::Triangle3D::setVertices (
    vec3 const _Vertices[3] ) [inline]
```

Set new vertices and update bounding box domain.

Parameters

<i>_Vertices</i>	Vertices reference vector
------------------	---------------------------

6.12.3.6 setVertices() [2/2]

```
void TireGround::RDF::Triangle3D::setVertices (
    vec3 const & Vertex0,
    vec3 const & Vertex1,
    vec3 const & Vertex2 ) [inline]
```

Set new vertices then update bounding box domain and normal versor.

Parameters

<i>Vertex0</i>	Vertex 1
<i>Vertex1</i>	Vertex 2
<i>Vertex2</i>	Vertex 3

The documentation for this class was generated from the following file:

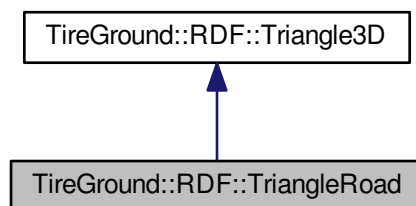
- include/RoadRDF.hh

6.13 TireGround::RDF::TriangleRoad Class Reference

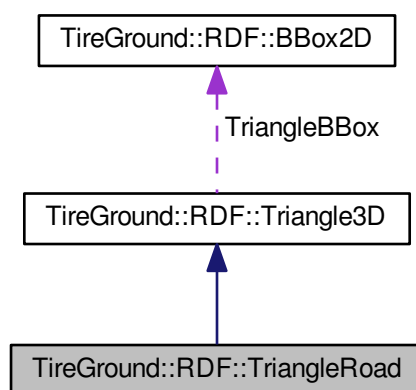
3D triangles for road representation

```
#include <RoadRDF.hh>
```

Inheritance diagram for TireGround::RDF::TriangleRoad:



Collaboration diagram for TireGround::RDF::TriangleRoad:



Public Member Functions

- [TriangleRoad](#) ()
Default set constructor.
- [TriangleRoad](#) ([vec3](#) const _Vertices[3], [real_type](#) _Friction)
Variable set constructor.
- void [setFriction](#) ([real_type](#) _Friction)

- *Set friction coefficient.*
 • `real_type getFriction (void) const`
- *Get friction coefficient on the face.*
 • `void setVertices (vec3 const _Vertices[3])`
- *Set new vertices and update bounding box domain.*
 • `void setVertices (vec3 const &Vertex0, vec3 const &Vertex1, vec3 const &Vertex2)`
- *Set new vertices then update bounding box domain and normal versor.*
 • `vec3 const & getNormal (void) const`
- *Get normal versor.*
 • `vec3 const & getVertex (unsigned i) const`
- *Get i-th vertex.*
 • `BBox2D const & getBBox (void) const`
- *Get Triangle3D bonding box BBox2D.*
 • `void print (ostream_type &stream) const`
- *Print vertices data.*
 • `bool intersectRay (vec3 const &RayOrigin, vec3 const &RayDirection, vec3 &IntPt) const`
- `int_type intersectEdgePlane (vec3 const &PlaneN, vec3 const &PlaneP, int_type const Edge, vec3 &IntPt1, vec3 &IntPt2) const`
- `bool intersectPlane (vec3 const &PlaneN, vec3 const &PlaneP, std::vector< vec3 > &IntPts) const`

Protected Attributes

- `vec3 Vertices [3]`
Vertices reference vector.
- `vec3 Normal`
Triangle normal versor.
- `BBox2D TriangleBBox`
Triangle 2D bounding box (XY plane)

6.13.1 Detailed Description

3D triangles for road representation

6.13.2 Constructor & Destructor Documentation

6.13.2.1 TriangleRoad()

```
TireGround::RDF::TriangleRoad::TriangleRoad (
    vec3 const _Vertices[3],
    real_type _Friction ) [inline]
```

Variable set constructor.

Parameters

<i>_Vertices</i>	Vertices reference vector
<i>_Friction</i>	Friction coefficient

6.13.3 Member Function Documentation

6.13.3.1 intersectEdgePlane()

```
int_type TireGround::RDF::Triangle3D::intersectEdgePlane (
    vec3 const & PlaneN,
    vec3 const & PlaneP,
    int_type const Edge,
    vec3 & IntPt1,
    vec3 & IntPt2 ) const [inherited]
```

Check if an edge of the [Triangle3D](#) object hits a and find the intersection point

Parameters

<i>PlaneN</i>	Plane normal vector
<i>PlaneP</i>	Plane known point
<i>Edge</i>	Triangle edge number (0:2)
<i>IntPt1</i>	Intersection point 1
<i>IntPt2</i>	Intersection point 2

6.13.3.2 intersectPlane()

```
bool TireGround::RDF::Triangle3D::intersectPlane (
    vec3 const & PlaneN,
    vec3 const & PlaneP,
    std::vector< vec3 > & IntPts ) const [inherited]
```

Check if a plane intersects a [Triangle3D](#) object and find the intersection points

Parameters

<i>PlaneN</i>	Plane normal vector
<i>PlaneP</i>	Plane known point
<i>IntPts</i>	Intersection points

6.13.3.3 intersectRay()

```
bool TireGround::RDF::Triangle3D::intersectRay (
    vec3 const & RayOrigin,
    vec3 const & RayDirection,
    vec3 & IntPt ) const [inherited]
```

Check if a ray hits a [Triangle3D](#) object through Möller-Trumbore intersection algorithm

Parameters

<i>RayOrigin</i>	Ray origin position
<i>RayDirection</i>	Ray direction vector
<i>IntPt</i>	Intersection point

6.13.3.4 print()

```
void TireGround::RDF::Triangle3D::print (
    ostream_type & stream ) const [inline], [inherited]
```

Print vertices data.

Parameters

<i>stream</i>	Output stream type
---------------	--------------------

6.13.3.5 setFriction()

```
void TireGround::RDF::TriangleRoad::setFriction (
    real_type _Friction ) [inline]
```

Set friction coefficient.

Parameters

<i>_Friction</i>	New friction coefficient
------------------	--------------------------

6.13.3.6 setVertices() [1/2]

```
void TireGround::RDF::Triangle3D::setVertices (
    vec3 const _Vertices[3] ) [inline], [inherited]
```

Set new vertices and update bounding box domain.

Parameters

<i>_Vertices</i>	Vertices reference vector
------------------	---------------------------

6.13.3.7 setVertices() [2/2]

```
void TireGround::RDF::Triangle3D::setVertices (
    vec3 const & Vertex0,
    vec3 const & Vertex1,
    vec3 const & Vertex2 ) [inline], [inherited]
```

Set new vertices then update bounding box domain and normal versor.

Parameters

<i>Vertex0</i>	Vertex 1
<i>Vertex1</i>	Vertex 2
<i>Vertex2</i>	Vertex 3

The documentation for this class was generated from the following file:

- include/RoadRDF.hh

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