

# Hardware-in-the-Loop Plant Modeling for Autonomous Vehicle

## Progress Presentation

Hannah Grady   Nicholas Nauman  
Advisor: Dr. Suruz Miah

Department of Electrical and Computer Engineering  
Bradley University  
1501 W. Bradley Avenue  
Peoria, IL, 61625, USA

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# Outline

- 1 Introduction
- 2 Steering Subsystem
- 3 Acceleration Subsystem
- 4 Brake Subsystem
- 5 Concluding Remarks
- 6 References

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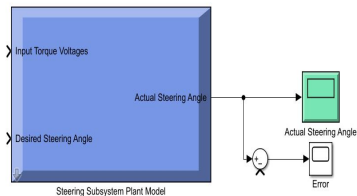
# Introduction

- Modeled
  - Steering Subsystem
  - Acceleration Pedal Subsystem
  - Brake Pedal Subsystem
- Not Modeled
  - Shift Subsystem
  - Speed Subsystem
  - Speed Control Subsystem
- Manual Data vs. By-Wire Data
- Neural Network Modeling [1] [2]

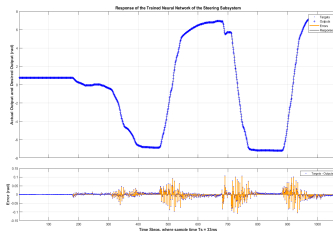
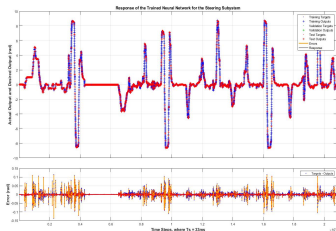
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# Steering Subsystem



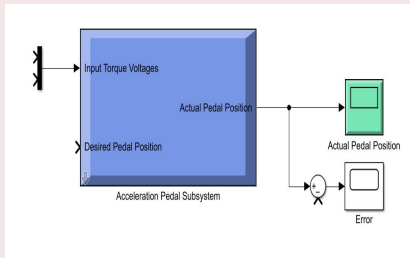
- Only a few samples are just outside of the accuracy requirements
- Transfer function model did not meet the accuracy requirements



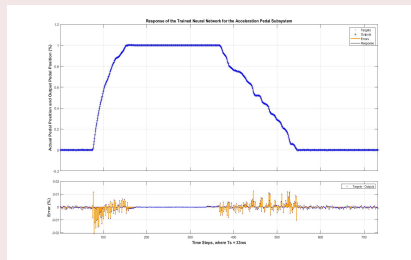
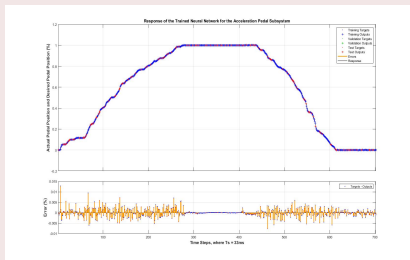
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# Acceleration Subsystem



- All samples within 2% of the actual output
- Transfer function model did not have the same accuracy bounds
- Fewer concerns about connections in Simulink





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## Brake Model

- System Identification Toolbox
- Neural Net Time Series Toolbox

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# Concluding Remarks

## Semester goals

- Test our modeled subsystems on the HIL bench
- Collect data for the remaining subsystems
- Model the remaining subsystems and test on the HIL bench
- Create final report highlighting our findings
- Present our findings

## Anticipated Challenges

- Having time to model the remaining subsystems
- Needing to correct any models

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# References I

- [1] V. Zhou, “Machine learning for beginners: An introduction to neural networks,” Dec 2019. [Online]. Available: <https://towardsdatascience.com/machine-learning-for-beginners-an-introduction-to-neural-networks-d49f2>
- [2] “Solve nonlinear time series problem using dynamic neural networks.” [Online]. Available: <https://www.mathworks.com/help/deeplearning/ref/neuralnettimeseries-app.html>