

simulation_continuous_sinusoidal_input

April 26, 2022

```
[ ]: import sys
      sys.path.append('../')
      from Driver import Driver
      from Race import Race
      from TMEasy import Tire
      from Vehicle import Vehicle
      from Track import Track
      import numpy as np
```

```
[ ]: %load_ext autoreload
      %autoreload 2
```

The autoreload extension is already loaded. To reload it, use:

```
%reload_ext autoreload
```

0.1 Tires

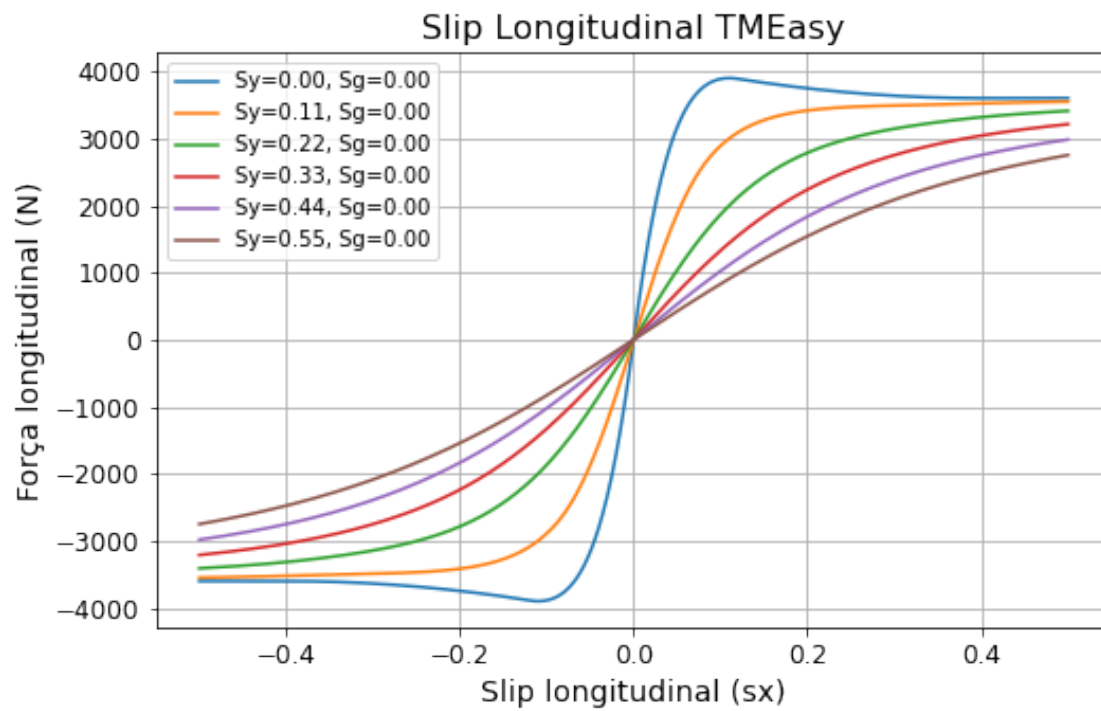
```
[ ]: radius = 0.293
      mass = 12
      Jz_tire = 1
      cz = 190000
      dfx0 = 100000
      dfy0 = 80000
      fxm = 3900
      fym = 3650
      sxm = 0.11
      sym = 0.16
      fxs = 3600
      fys = 3600
      sxs = 0.4
      sys = 0.5
      n2L0 = 0.18
      sy0 = 0.19
      syE = 0.35
      lamb = 2/3
      frr = 0.015
      TMEasy = Tire(radius, mass, Jz_tire, cz, dfx0, dfy0, fxm, fym, sxm, sym, fxs,
                    ↪fys, sxs, sys, sy0, syE, lamb, n2L0, frr)
```

```
TMEasy.all_info()
```

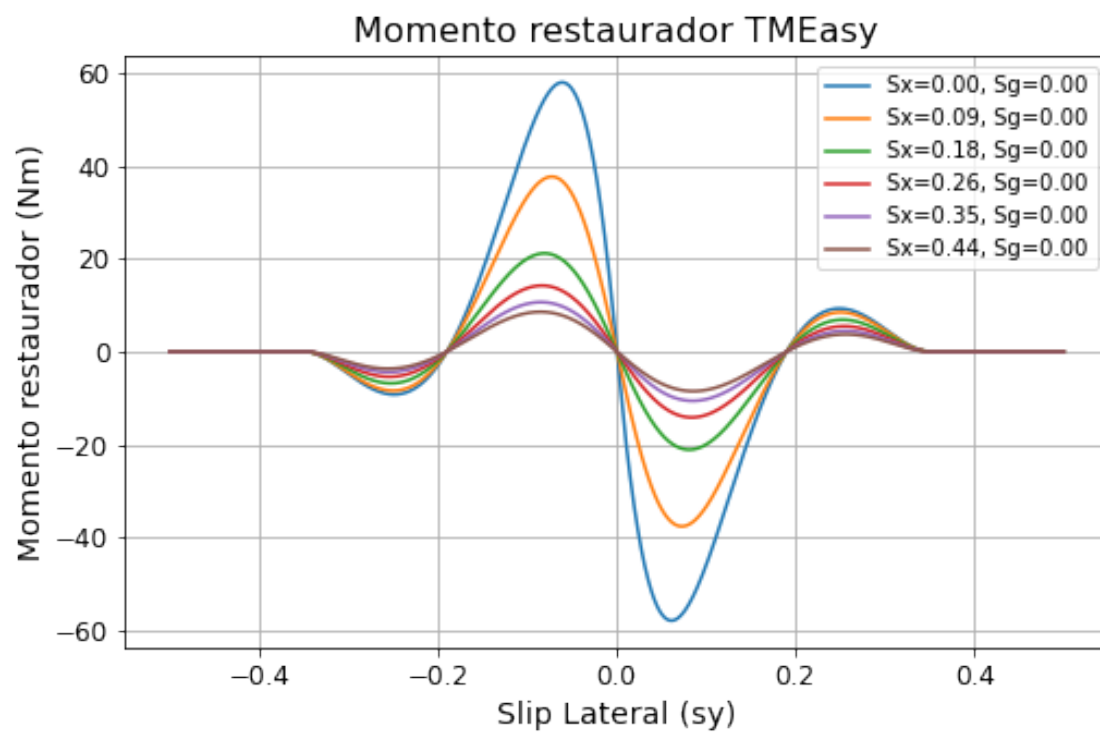
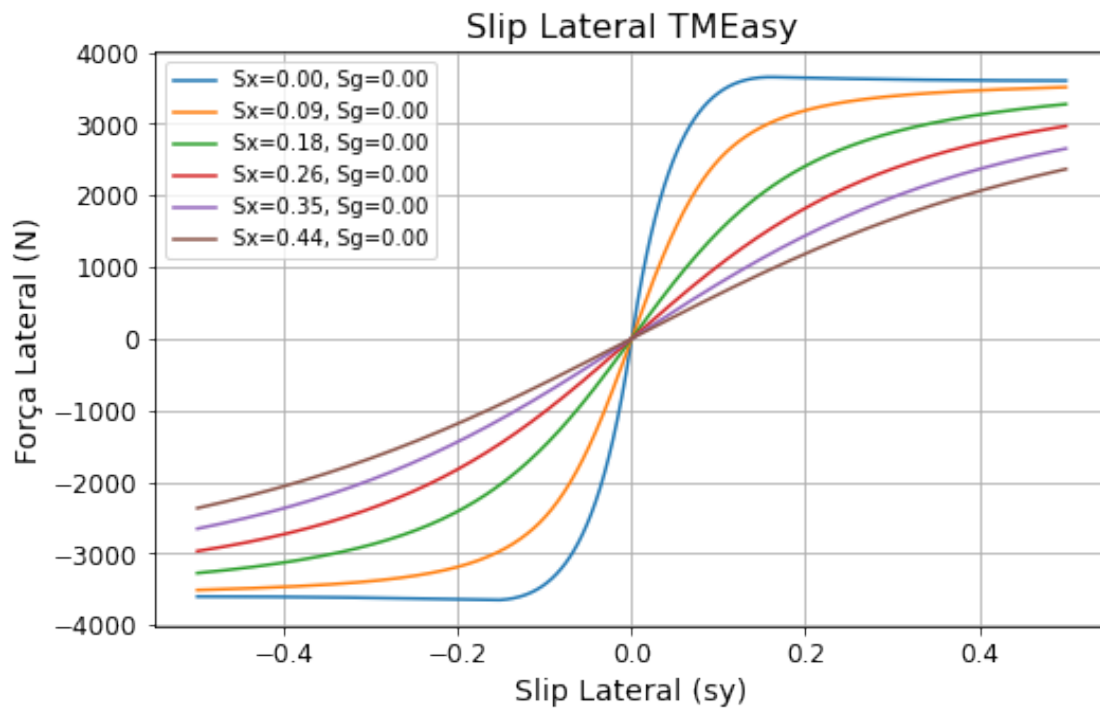
Vertical force considered: 3500N

Camber slip = 0.00

Bore slip = 0.00



Coenering stiffness = 1186.9N/



0.2 Driver

```
[ ]: driver = Driver(accelerator='PIDCSI', steering='sinusoidal')
      # driver = Driver(steer='S')
```

sinusoidal defined.

0.3 Track

```
[ ]: hx = 0
      hy = 0
      wx = 0.1
      wy = 100
      # mean = 0
      # variance = 1

      zf = lambda x, y: hx * np.sin(wx * x) + hy * np.sin(wy * y) #+ 0.01 * np.
          ↪ sin(10*x)
      vzf = lambda x, vx, y, vy: hx * wx * vx * np.cos(wx * x) + hy * wy * vy * np.
          ↪ cos(wy * y)

      track = Track(zf, vzf)
      # track.set_noise(mean, variance)
      track.profile(x=[0, 1000], y=[0,100], resolution=1)
```

0.4 Vehicle + Suspension

```
[ ]: vehicle_mass = 1742
      Ixx = 540
      Iyy = 2398
      Izz = 2617
      lf = 1.07
      lr = 1.605
      wf = 1.517
      wr = 1.505
      af = 2.17
      cd = 0.3
      CG_height = 0.503
      car = Vehicle(TMEasy, vehicle_mass, Ixx, Iyy, Izz, lf, lr, wf, wr, af, cd, ↪
          ↪ CG_height)
```

```
[ ]: K_sf = 30800
      K_sr = 28900
      C_sf = 4500
      C_sr = 3500
      car.set_suspension(K_sf, K_sr, C_sf, C_sr)

      G = 84e9
```

```

df = 0.022
af = 0.25
bf = 0.9
car.set_anti_roll_bar('f', df, af, bf, G)

dr = 0.013
ar = 0.3
br = 0.8
car.set_anti_roll_bar('r', dr, ar, br, G)

gamma1 = np.deg2rad(0) # 0 ângulo de cambagem positivo joga o carro para a
↳direita
gamma2 = np.deg2rad(0)
gamma3 = 0
gamma4 = 0
car.set_camber(gamma1, gamma2, gamma3, gamma4)

```

Anti-roll Bar (front) = 485.5 Nm/
 Anti-roll Bar (rear) = 36.5 Nm/

0.5 Simulation

```

[ ]: sim = Race(car, driver, track, maxTime=100, rtol=1e-3, atol=1e-3, maxStep=1e-2)
sim.post_process()

```

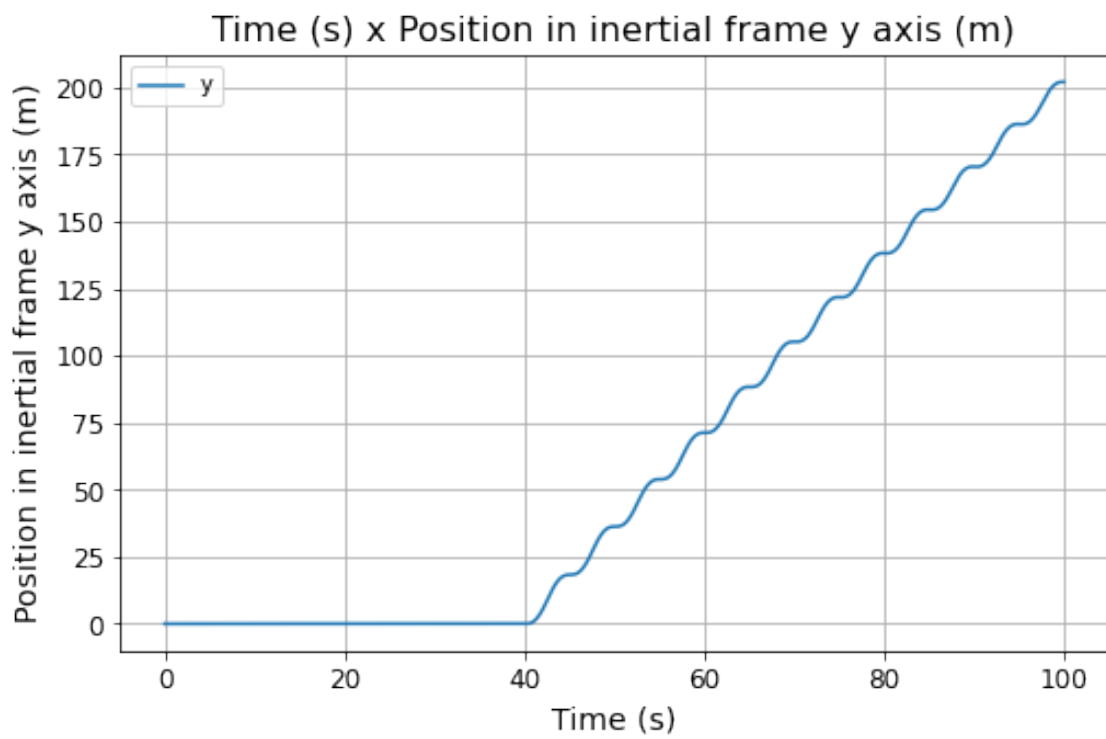
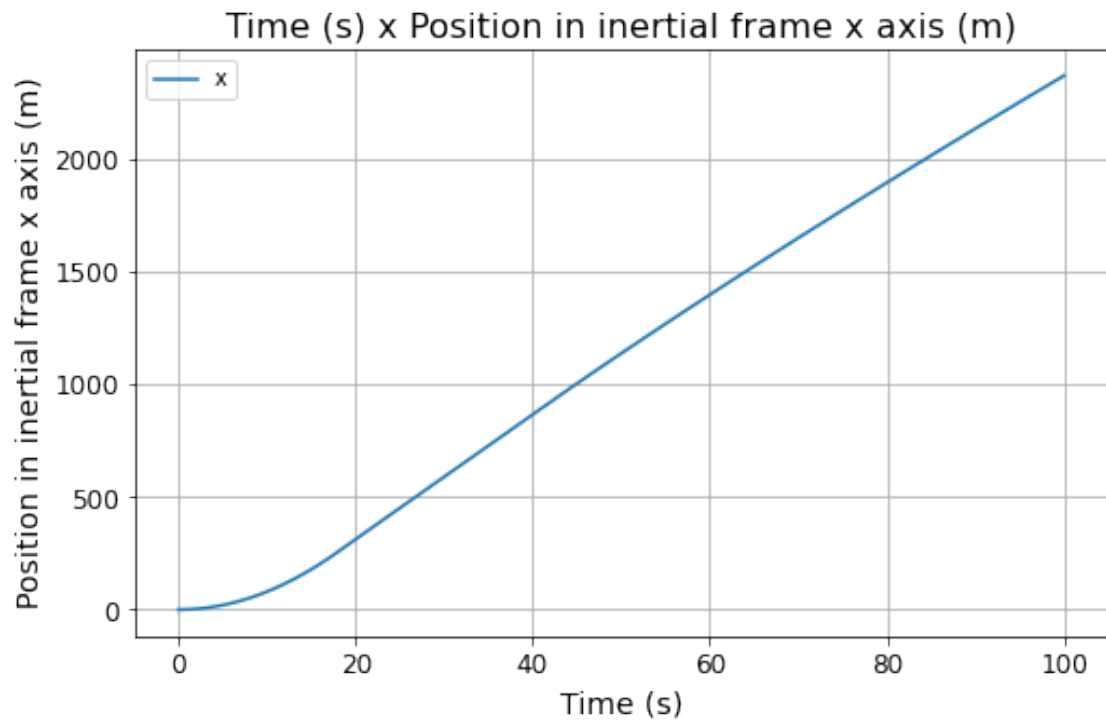
Solution Finished
 sinusoidal defined.

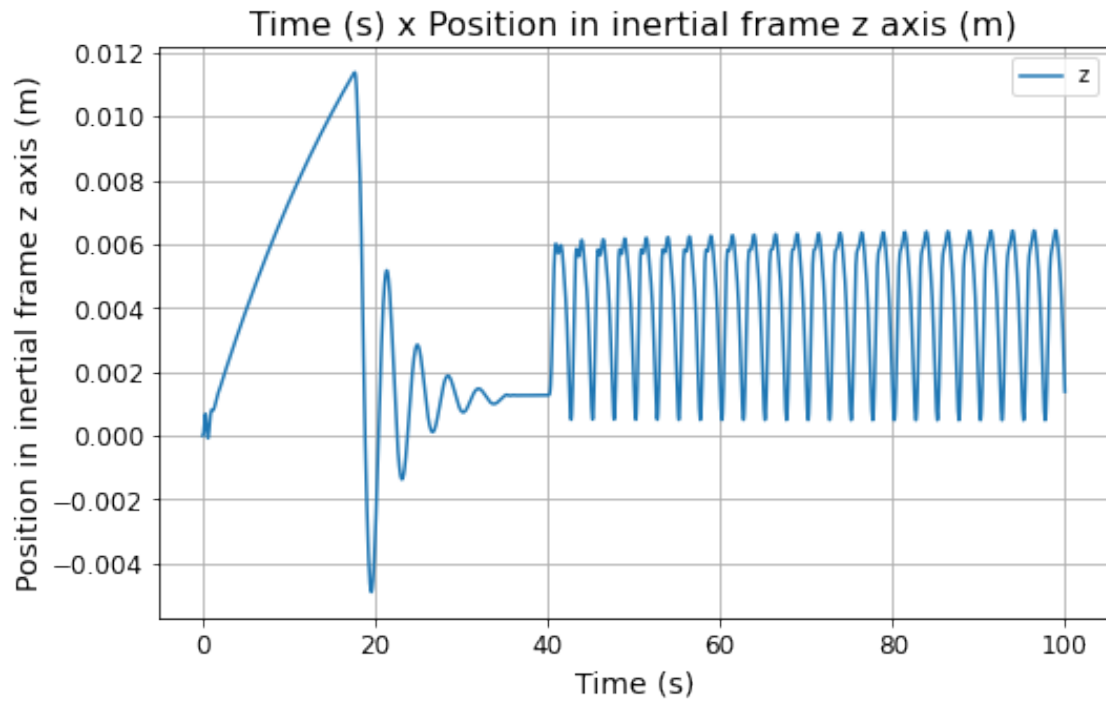
0.6 Position

```

[ ]: sim.x.plot2D()
sim.y.plot2D()
sim.z.plot2D()

```

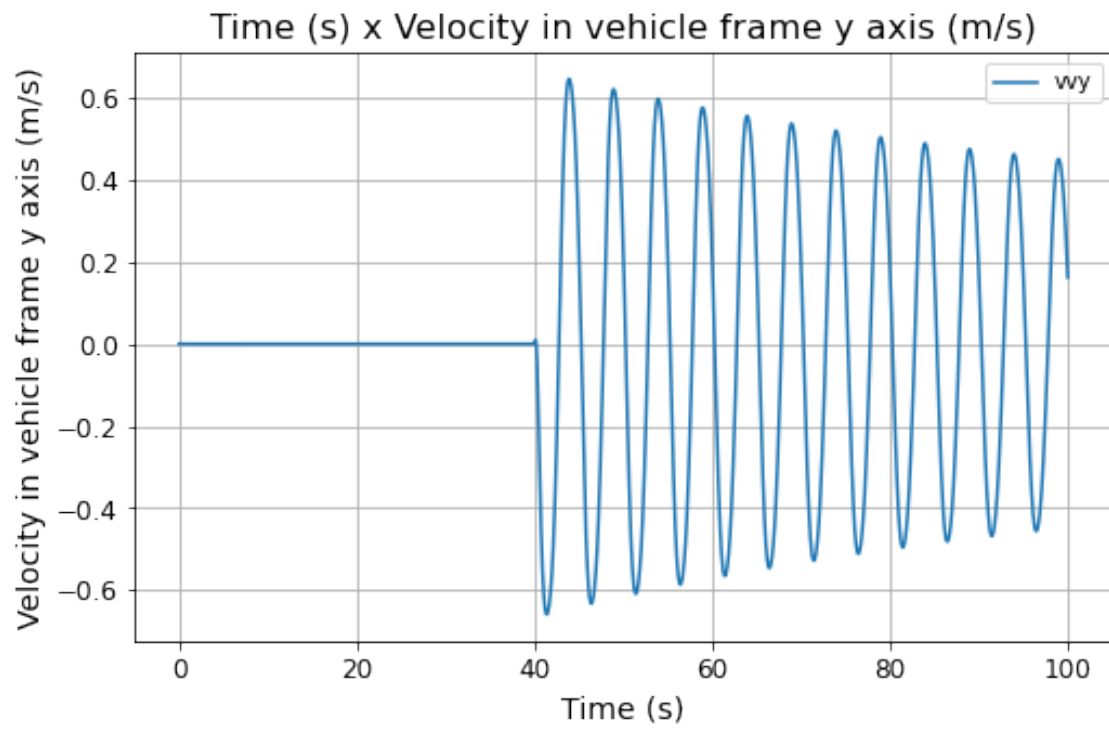
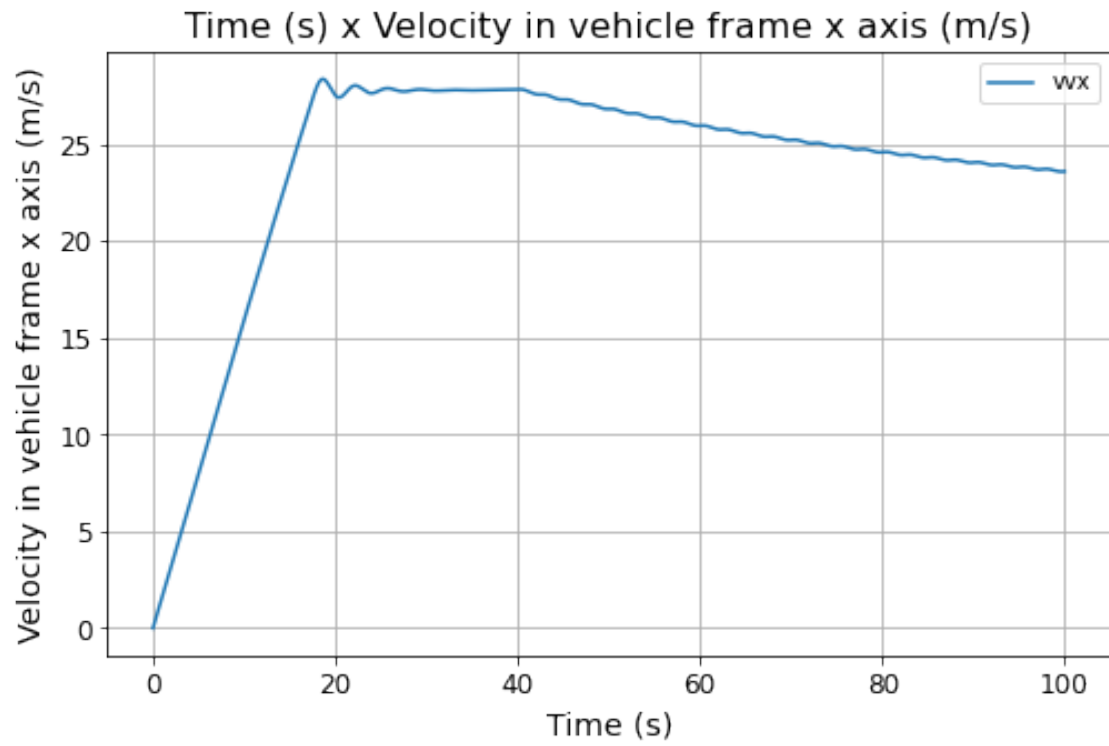


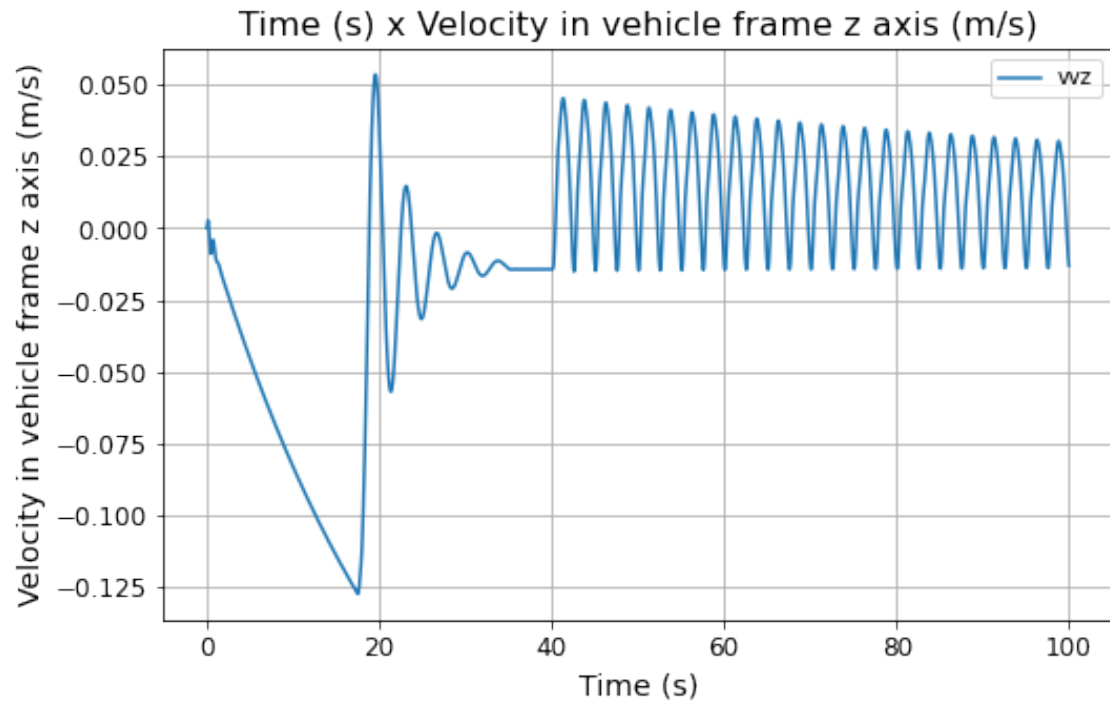


0.7 Speed

0.7.1 Vehicle frame

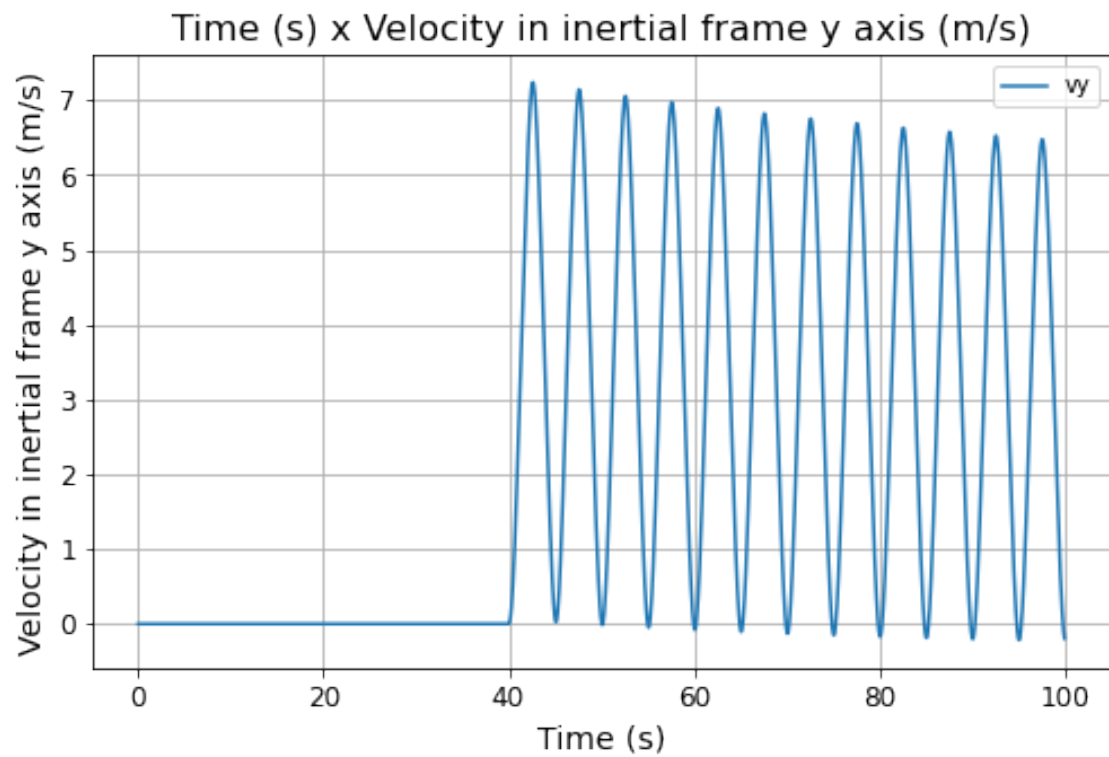
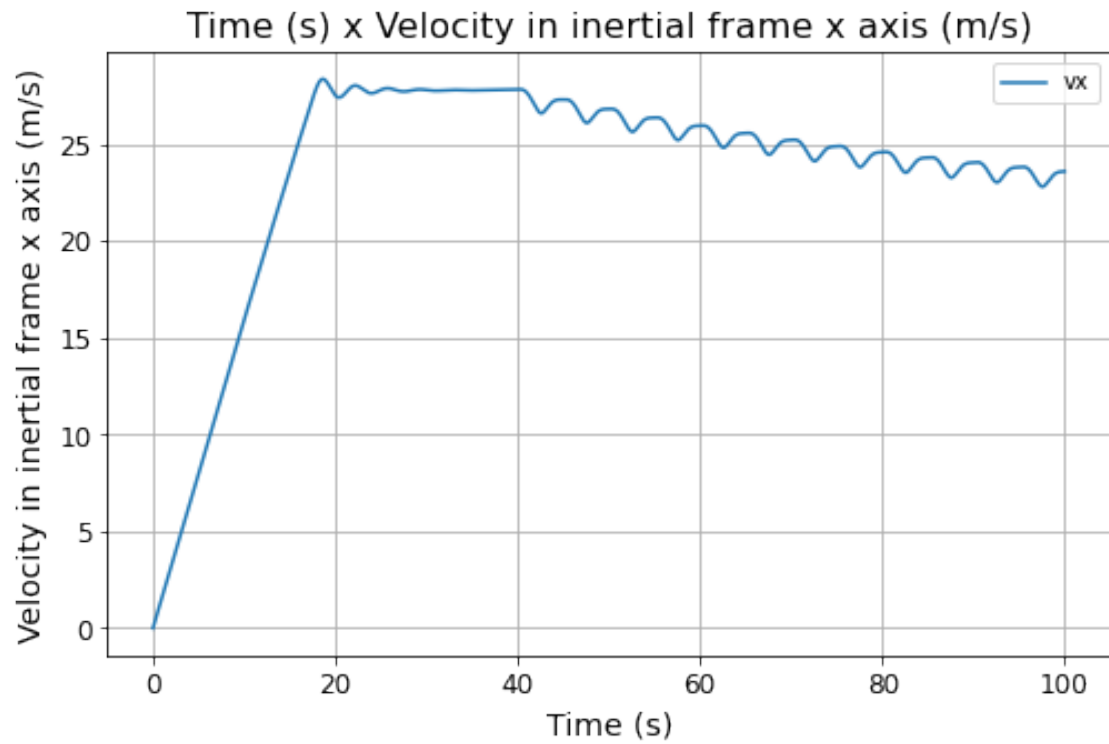
```
[ ]: sim.vvx.plot2D()  
     sim.vvy.plot2D()  
     sim.vvz.plot2D()
```

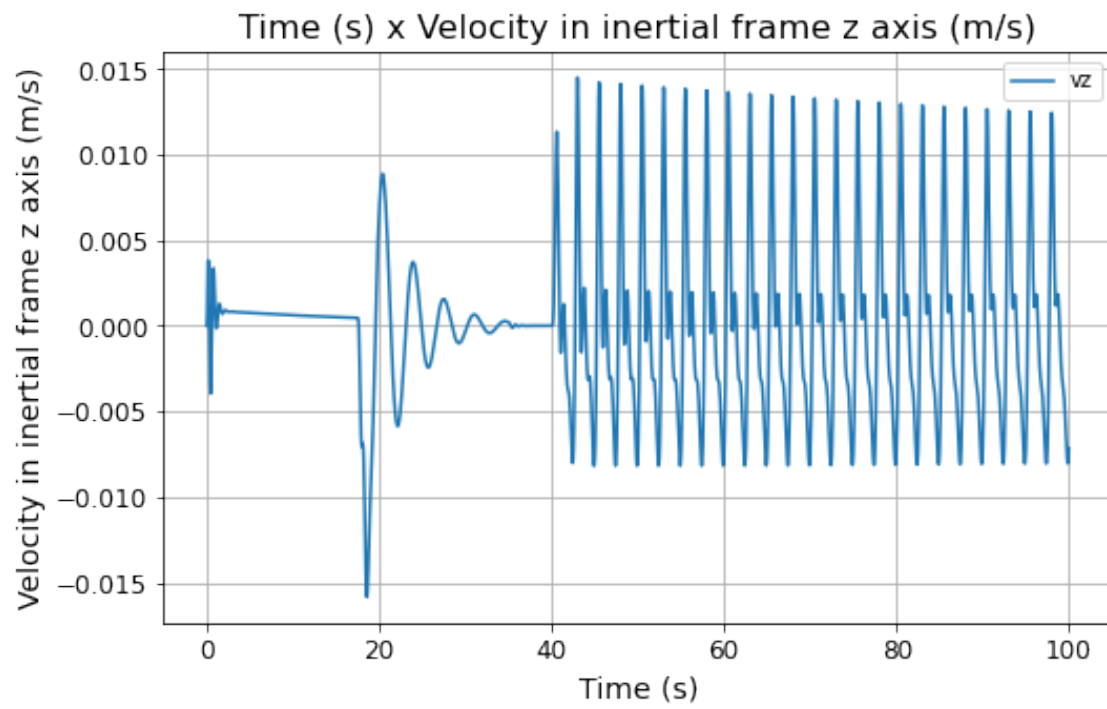




0.7.2 Inertial frame

```
[ ]: sim.vx.plot2D()  
     sim.vy.plot2D()  
     sim.vz.plot2D()
```

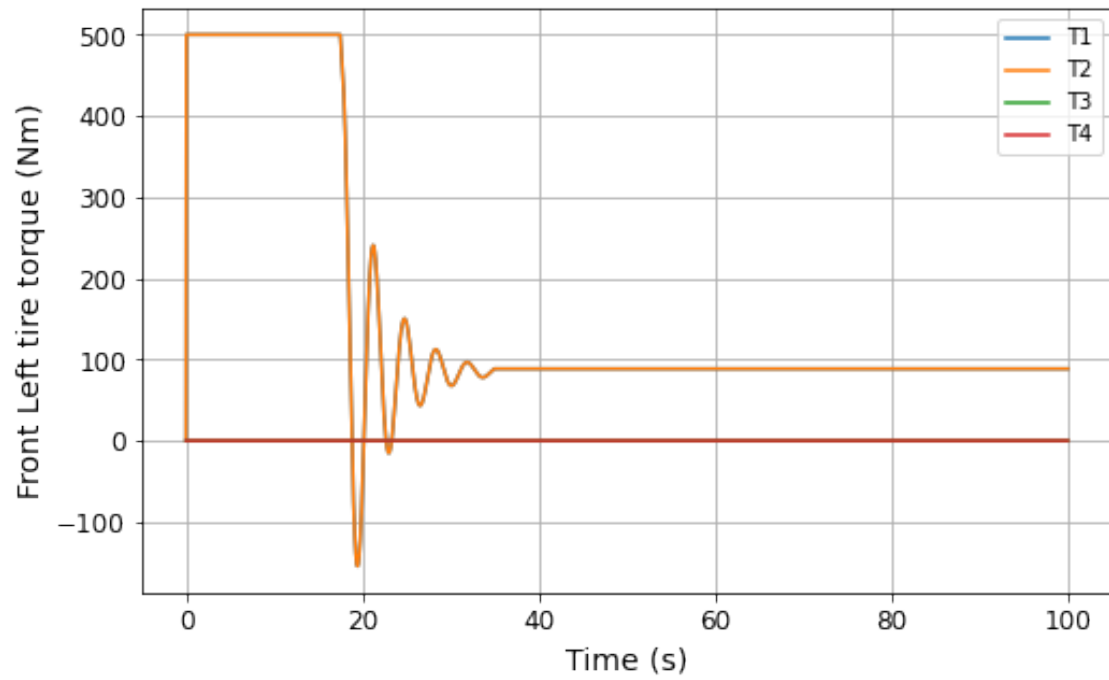




0.8 Acceleration

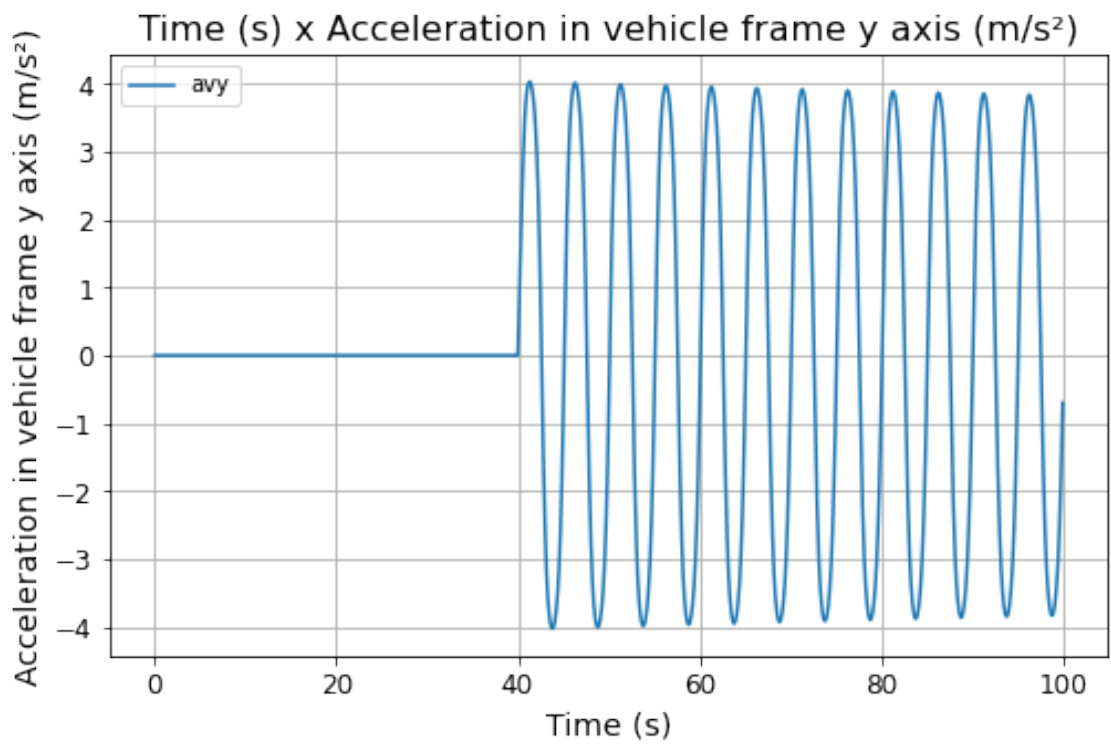
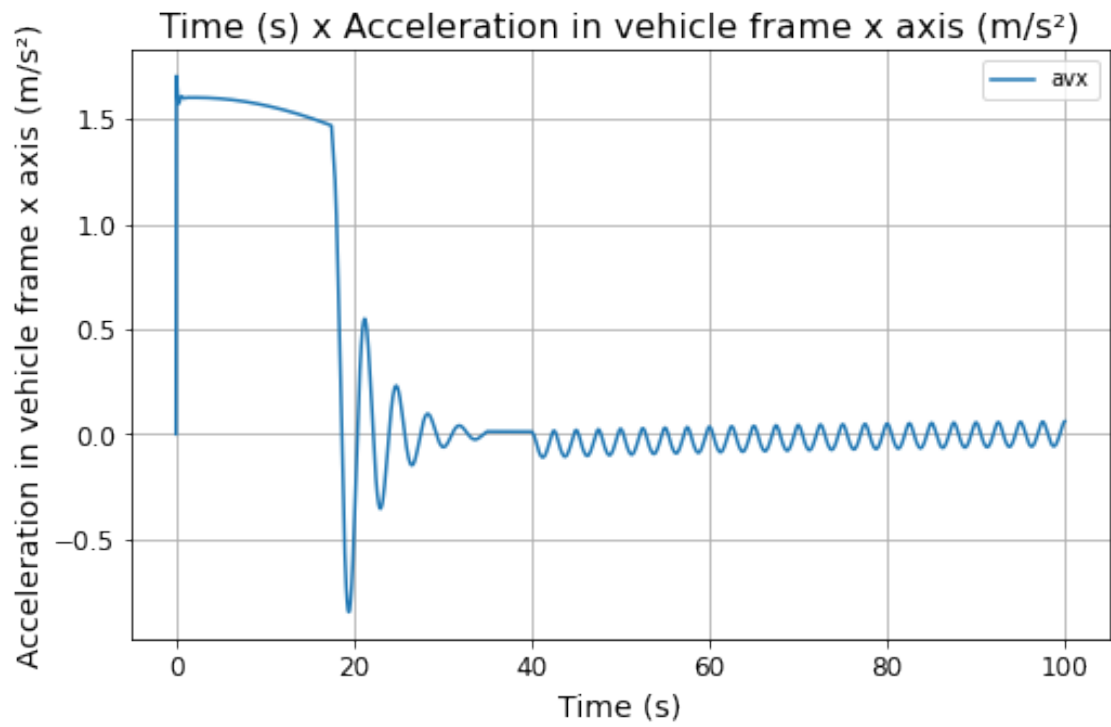
0.8.1 Input torque

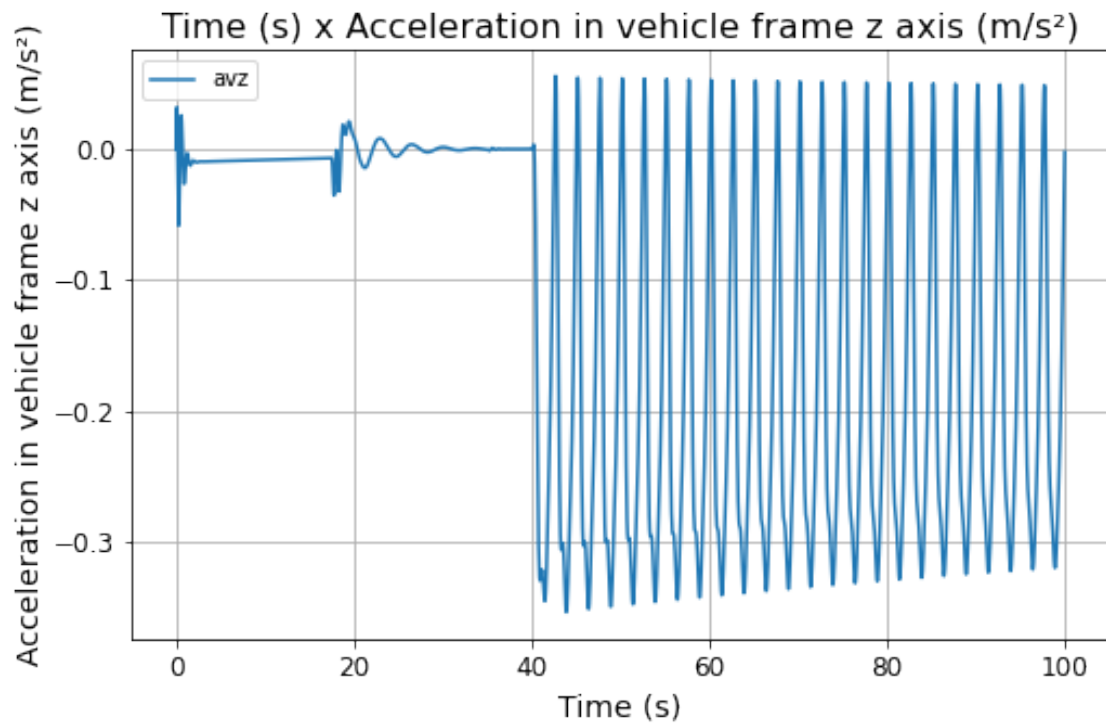
```
[ ]: sim.T1.comparaNPlots([sim.T2, sim.T3, sim.T4])
```



0.8.2 Vehicle Frame

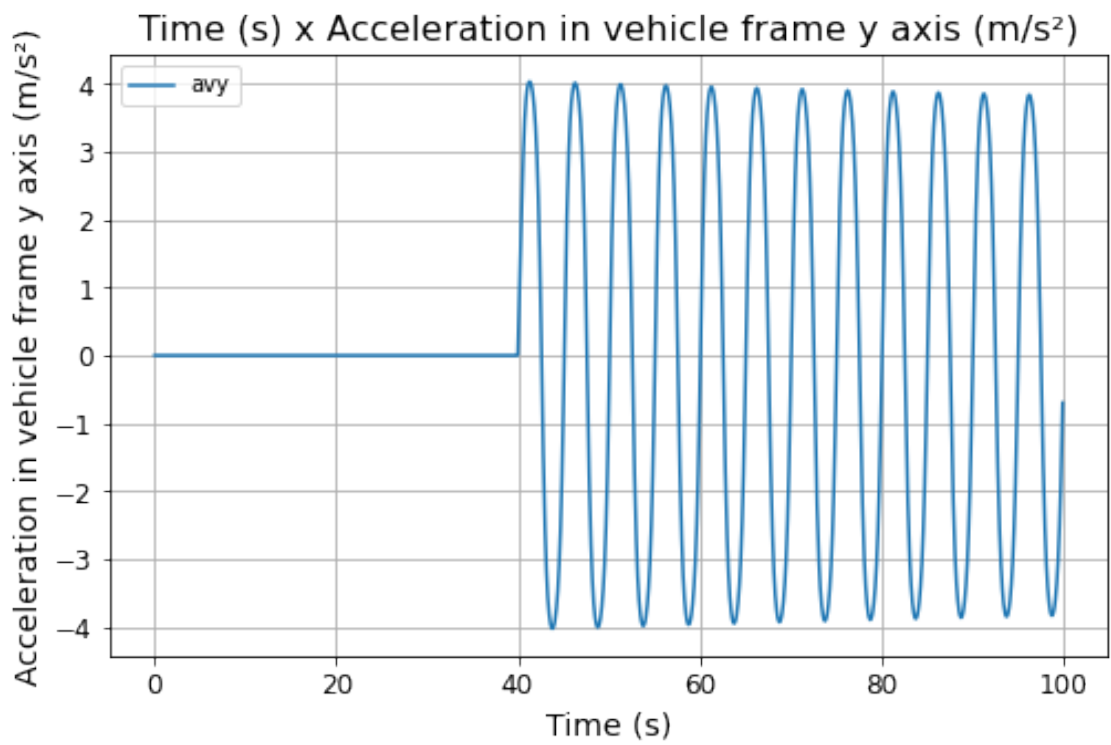
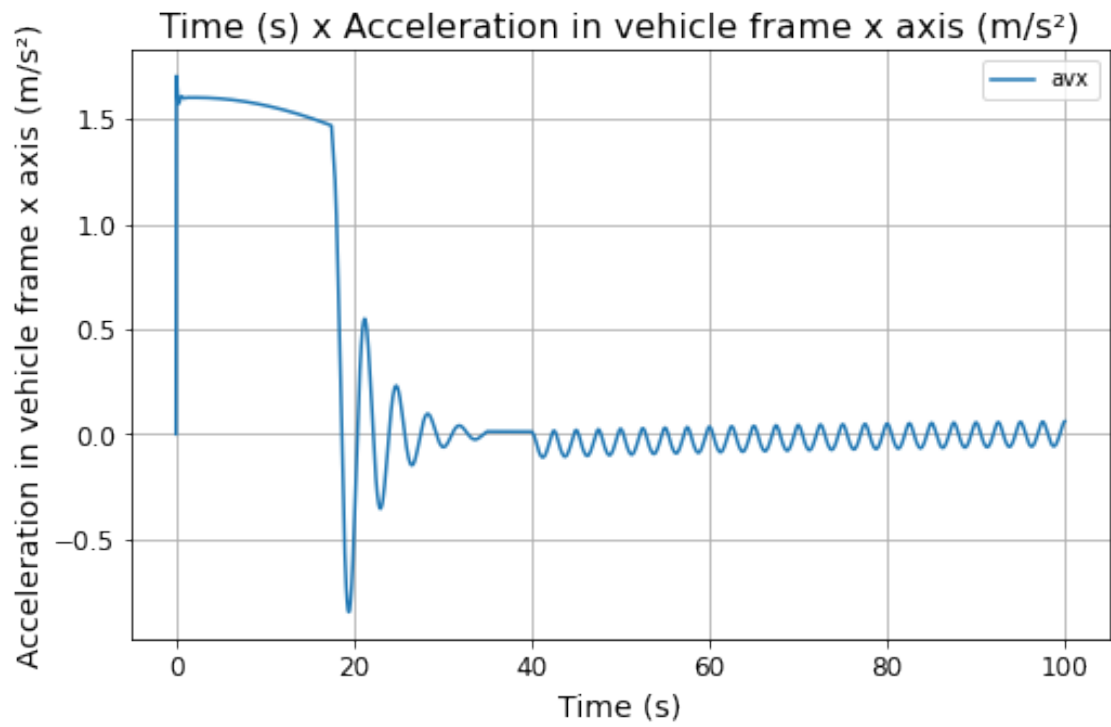
```
[ ]: sim.avx.plot2D()  
     sim.avy.plot2D()  
     sim.avz.plot2D()
```

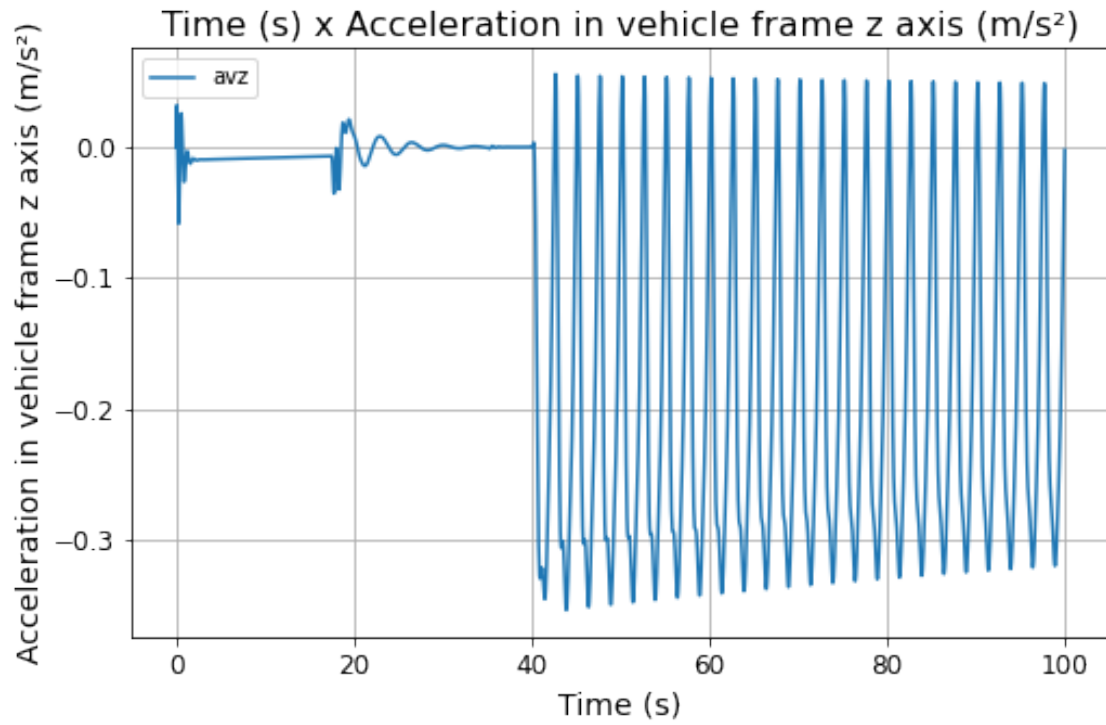




0.8.3 Inertial Frame

```
[ ]: sim.avx.plot2D()  
     sim.avy.plot2D()  
     sim.avz.plot2D()
```

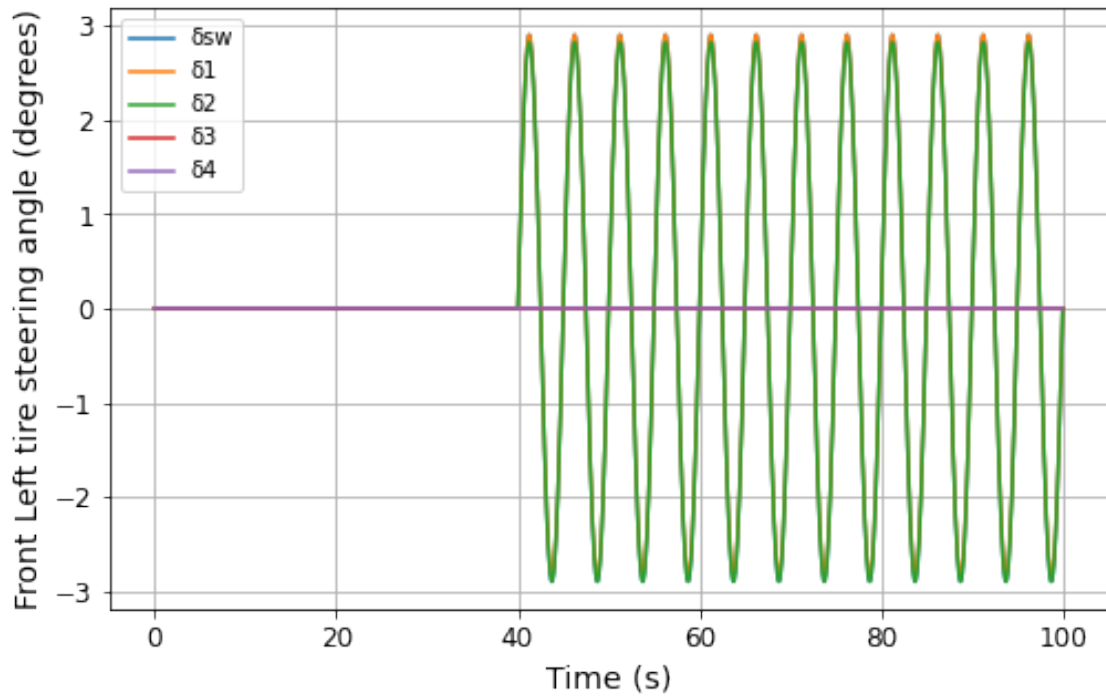




0.9 Tires

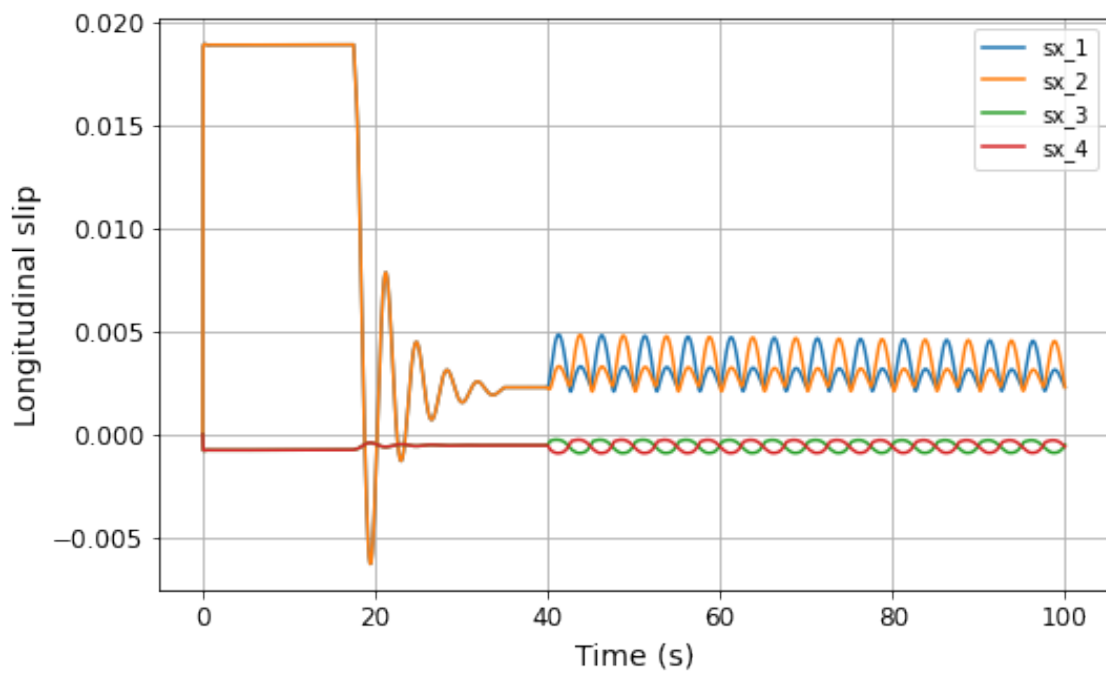
0.9.1 Delta

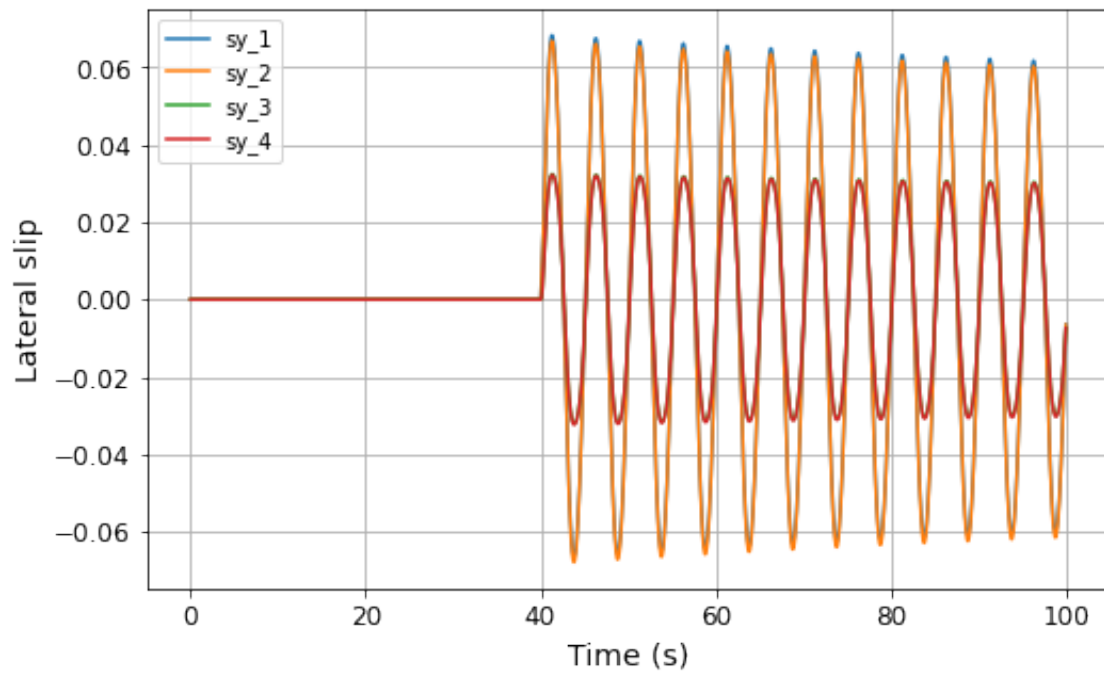
```
[ ]: sim.delta_sw.comparaNPlots([sim.delta_1, sim.delta_2, sim.delta_3, sim.delta_4])
```

0.9.2 Slips

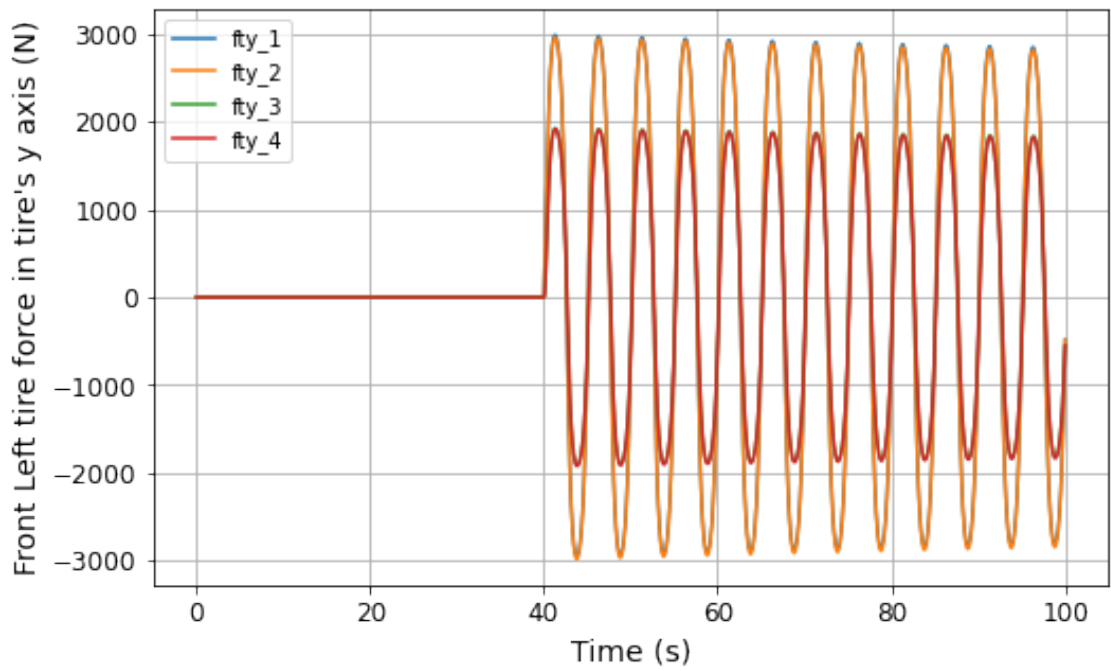
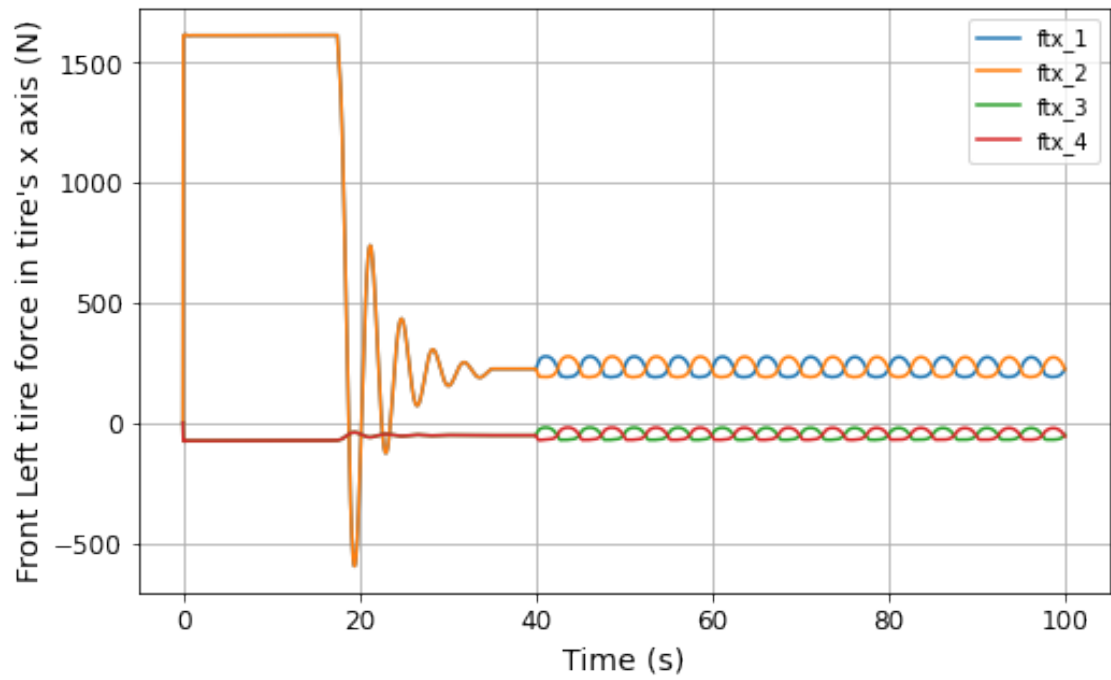
```
[ ]: sim.sx_1.comparaNPlots([sim.sx_2, sim.sx_3, sim.sx_4])
sim.sy_1.comparaNPlots([sim.sy_2, sim.sy_3, sim.sy_4])
```

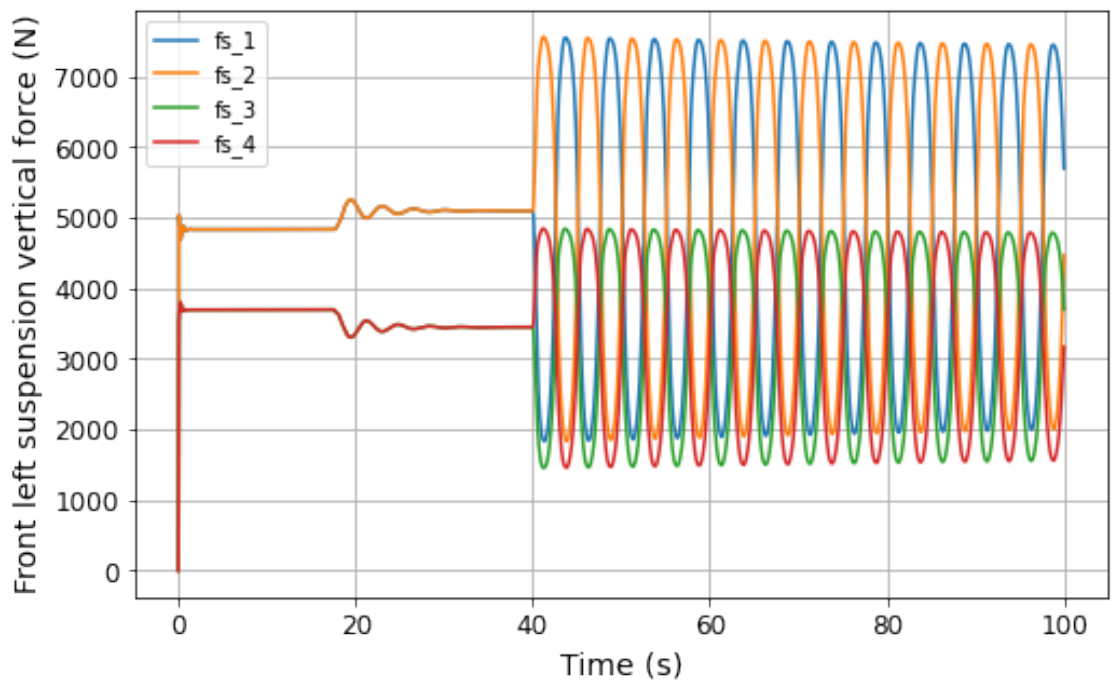
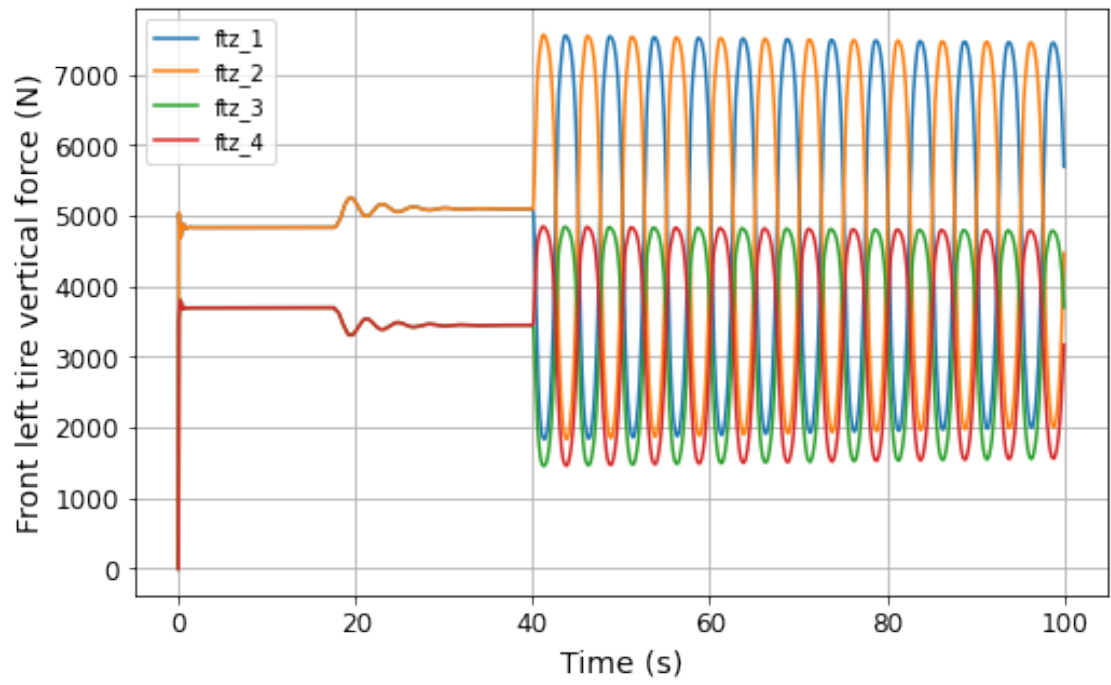




0.9.3 Forces

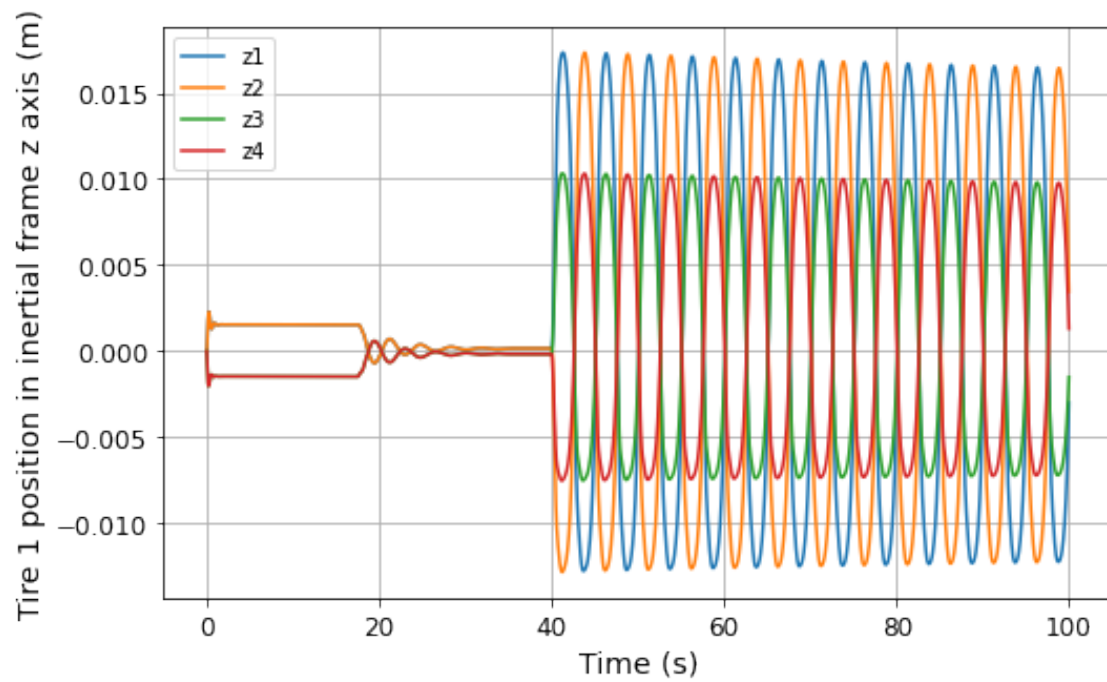
```
[ ]: sim.ftx_1.comparaNPlots([sim.ftx_2, sim.ftx_3, sim.ftx_4])
sim.fty_1.comparaNPlots([sim.fty_2, sim.fty_3, sim.fty_4])
sim.ftz_1.comparaNPlots([sim.ftz_2, sim.ftz_3, sim.ftz_4])
sim.fs_1.comparaNPlots([sim.fs_2, sim.fs_3, sim.fs_4])
```





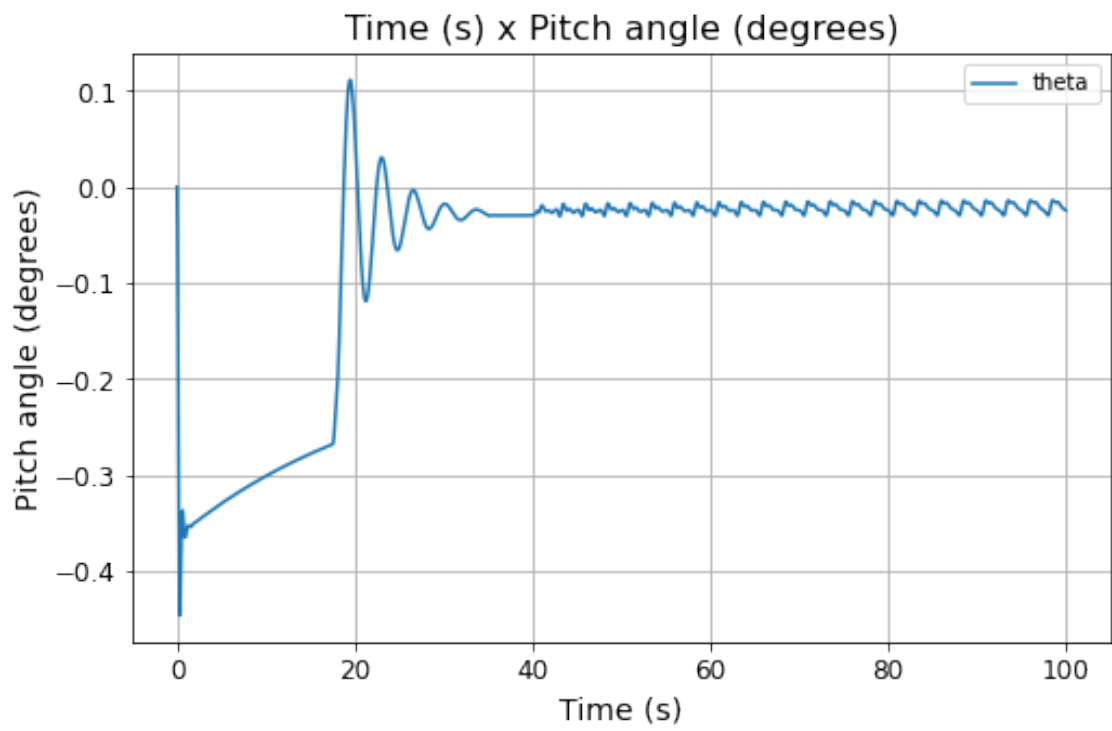
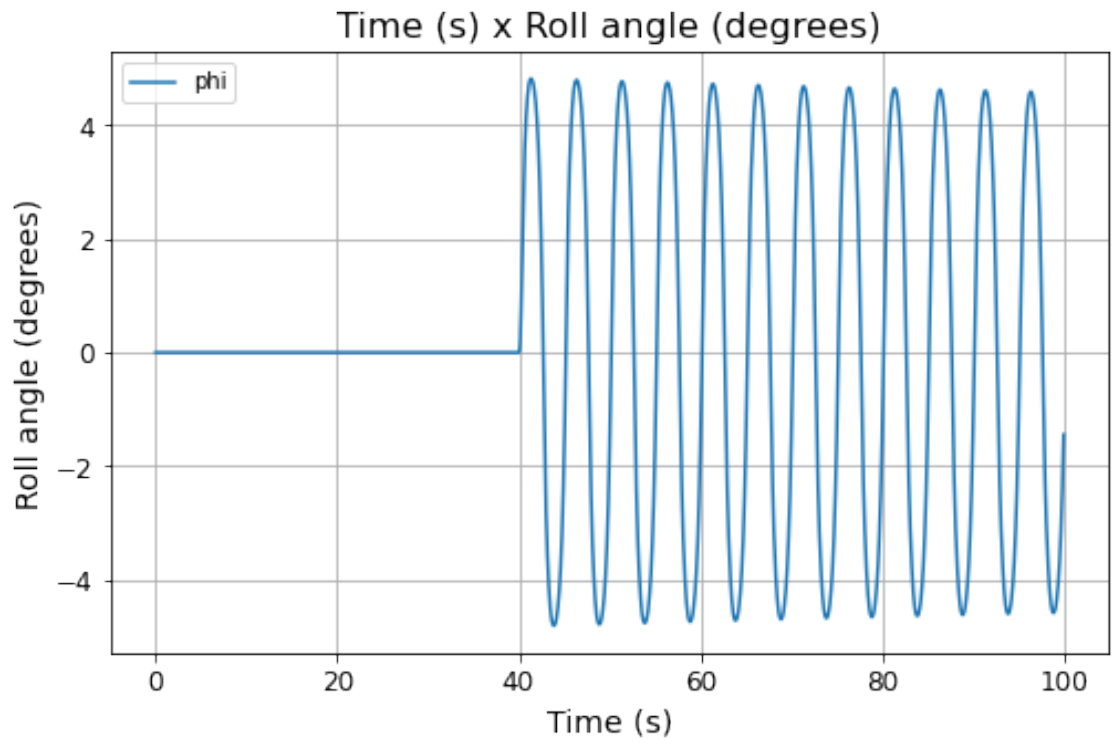
0.9.4 Tire height (z position)

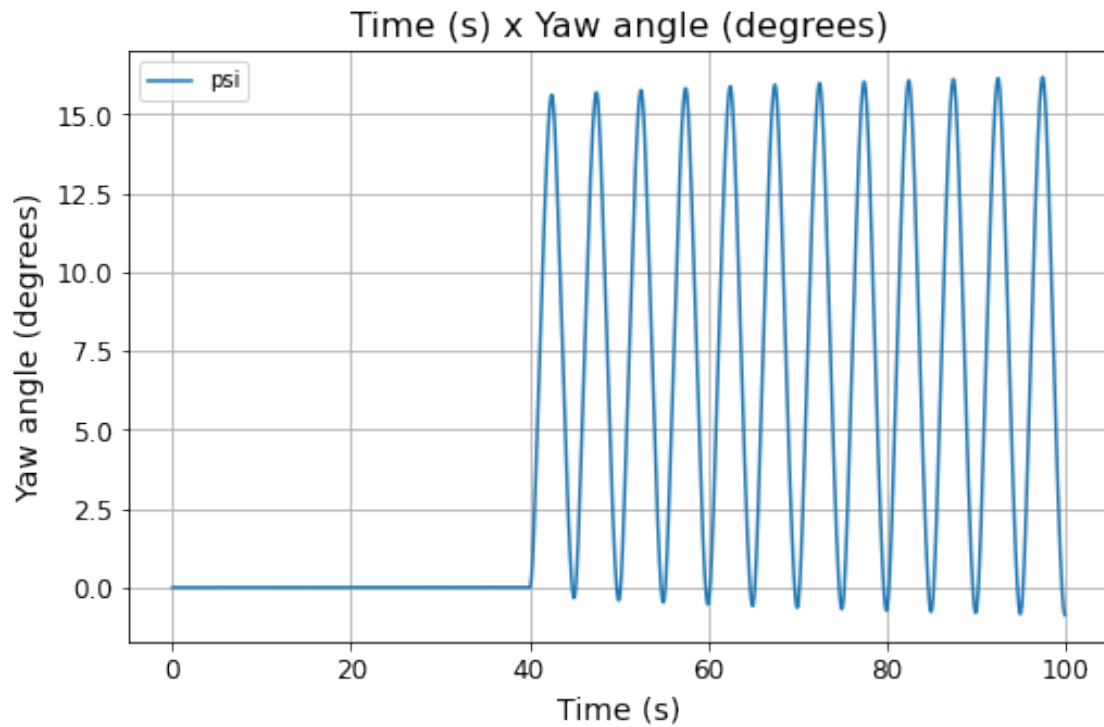
```
[ ]: sim.z1.comparaNPlots([sim.z2, sim.z3, sim.z4])
```



0.10 Angles

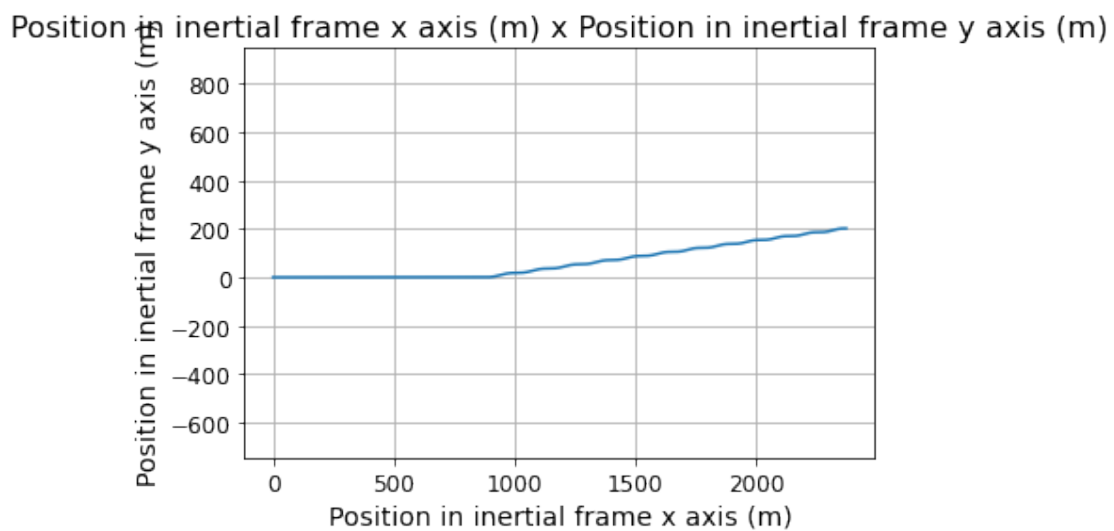
```
[ ]: sim.phi.plot2D()  
sim.theta.plot2D()  
sim.psi.plot2D()
```





0.11 Parametric

```
[ ]: sim.xy.plotparametric()
```



0.12 Animation

```
[ ]: # sim.animate(500, save=False)
```

```
[ ]:
```