

### State Equations:

$$\ddot{y} = -\dot{\psi}\dot{x} + \frac{2C_\alpha}{m} \left( \cos \delta \left( \delta - \frac{\dot{y} + l_f \dot{\psi}}{\dot{x}} \right) - \frac{\dot{y} - l_r \dot{\psi}}{\dot{x}} \right)$$

$$\ddot{x} = \dot{\psi}\dot{y} + \frac{1}{m}(F - fg)$$

$$\ddot{\psi} = \frac{2l_f C_\alpha}{I_z} \left( \delta - \frac{\dot{y} + l_f \dot{\psi}}{\dot{x}} \right) - \frac{2l_r C_\alpha}{I_z} \left( -\frac{\dot{y} - l_r \dot{\psi}}{\dot{x}} \right)$$

$$\dot{X} = \dot{x} \cos \psi - \dot{y} \sin \psi$$

$$\dot{Y} = \dot{x} \sin \psi + \dot{y} \cos \psi$$

### Measurements:

$$y = \begin{bmatrix} \dot{x} \\ \dot{y} \\ \dot{\psi} \\ X \\ Y \\ \psi \end{bmatrix}$$

### Model Parameters:

$$\delta \leq \frac{\pi}{6} \text{ rad}$$

$$F \geq 0 \text{ and } F \leq 15367 \text{ N}$$

$$x \geq 10^{-5} \text{ m/s}$$

Name	Description	Unit	Value
$(\dot{x}, \dot{y})$	Vehicle's velocity along the direction of vehicle frame	$m/s$	State
$(X, Y)$	Vehicle's coordinates in the world frame	$m$	State
$\psi, \dot{\psi}$	Body yaw angle, angular speed	$rad, rad/s$	State
$\delta, \delta_f$	Front wheel angle	$rad$	Input
$F$	Total input force	$N$	Input
$m$	Vehicle mass	$kg$	1888.6
$l_r$	Length from rear tire to the center of mass	$m$	1.39
$l_f$	Length from front tire to the center of mass	$m$	1.55
$C_\alpha$	Cornering stiffness of each tire	$N$	20000
$I_z$	Yaw inertia	$kg \cdot m^2$	25854

$F_{pq}$	Tire Force, $p \in \{x, y\}, q \in \{f, r\}$	$N$	Depends on input force
$f$	Rolling resistance coefficient	$N/A$	0.019
$delT$	Simulation timestep	$sec$	0.032

## I. Linearization

### Lateral Linearization

$$u = \begin{bmatrix} \delta \\ F \end{bmatrix}, s_1 = \begin{bmatrix} y \\ \dot{y} \\ \psi \\ \dot{\psi} \end{bmatrix}$$

Assume  $x, \dot{x}$  are constant in the lateral system.

$$\text{Let } \dot{x} = v_x$$

Non-linearized System:

$$\dot{s}_1 = \begin{bmatrix} \dot{y} \\ \ddot{y} \\ \dot{\psi} \\ \ddot{\psi} \end{bmatrix} = \begin{bmatrix} \dot{y} \\ -\dot{\psi}v_x + \frac{2C_\alpha}{m} \left( \cos \delta \left( \delta - \frac{\dot{y} + l_f \dot{\psi}}{v_x} \right) - \frac{\dot{y} - l_r \dot{\psi}}{v_x} \right) \\ \dot{\psi} \\ \frac{2l_f C_\alpha}{I_z} \left( \delta - \frac{\dot{y} + l_f \dot{\psi}}{v_x} \right) - \frac{2l_r C_\alpha}{I_z} \left( -\frac{\dot{y} - l_r \dot{\psi}}{v_x} \right) \end{bmatrix} = f(s_1, u)$$

$$A_1 = \nabla f_{s_1}, B_1 = \nabla f_u$$

$$A_1 = \begin{bmatrix} 0 & 1 & 0 & 0 \\ 0 & -\frac{2C_\alpha}{mv_x}(\cos \delta + 1) & 0 & -v_x + \frac{2C_\alpha}{mv_x}(-l_f \cos \delta + l_r) \\ 0 & 0 & 1 & 0 \\ 0 & \frac{2C_\alpha}{I_z v_x}(l_r - l_f) & 0 & \frac{2C_\alpha}{I_z v_x}(-l_f^2 - l_r^2) \end{bmatrix}$$

$$B_1 = \begin{bmatrix} 0 & 0 \\ \frac{2C_\alpha}{m} \left( -\sin \delta \left( \delta - \frac{\dot{y} + l_f \dot{\psi}}{v_x} \right) + \cos \delta \right) & 0 \\ 0 & 0 \\ \frac{2l_f C_\alpha}{I_z} & 0 \end{bmatrix}$$

Apply small angle Approximations  $\rightarrow \cos(\delta) \approx 1, \sin(\delta) \approx 0$

$$A_1 = \begin{bmatrix} 0 & 1 & 0 & 0 \\ 0 & -\frac{4C_\alpha}{mv_x} & 0 & -v_x - \frac{2C_\alpha}{mv_x}(l_f - l_r) \\ 0 & 0 & 1 & 0 \\ 0 & \frac{2C_\alpha}{I_z v_x}(l_r - l_f) & 0 & -\frac{2C_\alpha}{I_z v_x}(l_f^2 + l_r^2) \end{bmatrix}$$

$$B_1 = \begin{bmatrix} 0 & 0 \\ \frac{2C_\alpha}{m} & 0 \\ 0 & 0 \\ \frac{2l_f C_\alpha}{I_z} & 0 \end{bmatrix}$$

### Longitudinal Linearization

$$u = \begin{bmatrix} \delta \\ F \end{bmatrix}, s_2 = \begin{bmatrix} x \\ \dot{x} \end{bmatrix}$$

Assume  $y, \dot{y}, \psi, \dot{\psi}$ , are constant in the longitudinal linearization

Non-linearized System:

$$\dot{s}_2 = \begin{bmatrix} \dot{x} \\ \ddot{x} \end{bmatrix} = \begin{bmatrix} \dot{x} \\ \dot{\psi}\dot{y} + \frac{1}{m}(F - fg) \end{bmatrix}$$

$$A_2 = \nabla f_{s_2}, B_1 = \nabla f_2$$

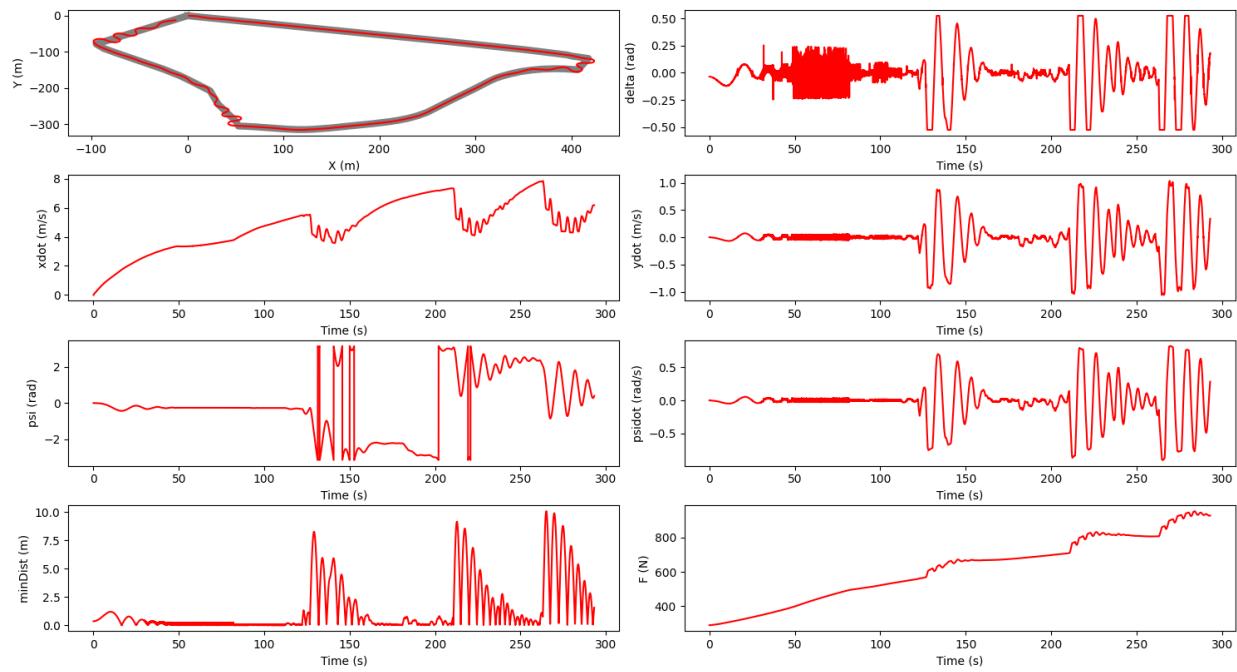
$$A_2 = \begin{bmatrix} 0 & 1 \\ 0 & 0 \end{bmatrix}$$

$$B_2 = \begin{bmatrix} 0 & 0 \\ 0 & \frac{1}{m} \end{bmatrix}$$

Dynamics of rolling accommodate for using a disturbance term

$$d(t) = \begin{bmatrix} 0 \\ \dot{\psi}\dot{y} + \frac{fg}{m} \end{bmatrix}$$

## PID Results:



**Fig.1 Simulation Plot**



**Fig.2 Simulation Result**

## Twiddle Algorithm for PID tuning

```
import numpy as np
from util import getTrajectory, closestNode, clamp

default_dt = 0.032

class PID:
    def __init__(self, Kp, Ki, Kd, dt=default_dt):
        self.Kp = Kp
        self.Ki = Ki
        self.Kd = Kd
        self.dt = dt
        self.integral = 0
        self.prev_error = 0

    def reset(self):
        self.integral = 0
        self.prev_error = 0

    def update(self, setpoint, measurement):
        error = setpoint - measurement
        self.integral += error * self.dt
        derivative = (error - self.prev_error) / self.dt
        output = self.Kp * error + self.Ki * self.integral + self.Kd * derivative
        self.prev_error = error
        return output

# Load trajectory using util.py
trajectory = getTrajectory('buggyTrace.csv')

# Simulate lateral controller (returns total squared cross-track error)
def lateral_error(pid_gains, trajectory, dt=default_dt):
    Kp, Ki, Kd = pid_gains
    pid = PID(Kp, Ki, Kd, dt)
    X, Y = trajectory[0, 0], trajectory[0, 1] # start at first waypoint
    total_error = 0
    for i in range(1, len(trajectory)):
        cross_track_error, idx = closestNode(X, Y, trajectory)
        control = pid.update(0, cross_track_error) # setpoint is 0
        # Simulate: move towards next waypoint, apply steering
        direction = trajectory[i] - np.array([X, Y])
        speed = 11 #
        max_steer = np.radians(30)
        control = clamp(control, -max_steer, max_steer)
```

```

        X += direction[0] * dt + control * dt
        Y += direction[1] * dt + control * dt
        total_error += cross_track_error ** 2
    return total_error

# Simulate longitudinal controller (returns total squared speed error)
def longitudinal_error(pid_gains, trajectory, desired_speed=11.0, dt=default_dt):
    Kp, Ki, Kd = pid_gains
    pid = PID(Kp, Ki, Kd, dt)
    speed = 0.0
    total_error = 0
    for i in range(1, len(trajectory)):
        speed_error = desired_speed - speed
        control = pid.update(desired_speed, speed)
        # Simulate: update speed
        speed += control * dt
        speed = clamp(speed, 0, 50) # clamp to reasonable speed range
        total_error += speed_error ** 2
    return total_error

# Twiddle algorithm for PID tuning
def twiddle(error_func, trajectory, tol=0.01, initial_p=[0.00, 0.0, 0.0],
initial_dp=[0.01, 0.01, 0.01]):
    p = initial_p.copy()
    dp = initial_dp.copy()
    best_err = error_func(p, trajectory)
    it = 0
    prev_err = None
    while sum(dp) > tol:
        for i in range(len(p)):
            p[i] += dp[i]
            err = error_func(p, trajectory)
            if err < best_err:
                best_err = err
                dp[i] *= 1.1
            else:
                p[i] -= 2 * dp[i]
                err = error_func(p, trajectory)
                if err < best_err:
                    best_err = err
                    dp[i] *= 1.05
                else:
                    p[i] += dp[i]
                    dp[i] *= 0.95
        it += 1

```

```
print(f"Iteration {it}, PID: {p}, Error: {best_err}")
# Stop if error does not change
if prev_err is not None and abs(best_err - prev_err) < 1e-8:
    print("Error did not change, stopping Twiddle.")
    break
prev_err = best_err
return p

if __name__ == "__main__":
    print("Tuning lateral PID...")
    best_pid_lateral = twiddle(lateral_error, trajectory)
    print("Best lateral PID gains:", best_pid_lateral)
    # dp's set to 0.1 - Best lateral PID gains: [0.1, 0.0, 0.0]
    # dp s set to 0.01 - Best lateral PID gains: [0.1143588810000004, 0.0,
0.0178966525]
    print("Tuning longitudinal PID...")
    best_pid_longitudinal = twiddle(longitudinal_error, trajectory)
    print("Best longitudinal PID gains:", best_pid_longitudinal)
    # dp's set to 0.1- Best longitudinal PID gains: [29.91268053287073,
1.3640345468017792, 0.02870992997411423]
    # dp's set to 0.01 -Best longitudinal PID gains: [27.580149049219923,
0.4822354299071474, 0.0734521331616762]
```

## Tuned PID Controller:

```
# Import libraries
import numpy as np
from base_controller import BaseController
from scipy import signal, linalg
from util import *

class PID:
    def __init__(self, Kp, Ki, Kd, dt):
        self.Kp = Kp
        self.Ki = Ki
        self.Kd = Kd
        self.dt = dt
        self.integral = 0
        self.prev_error = 0

    def reset(self):
        self.integral = 0
        self.prev_error = 0

    def update(self, setpoint, measurement):
        error = setpoint - measurement
        self.integral += error * self.dt
        derivative = (error - self.prev_error) / self.dt
        output = self.Kp * error + self.Ki * self.integral + self.Kd * derivative
        self.prev_error = error
        return output

# CustomController class (inherits from BaseController)
class CustomController(BaseController):

    def __init__(self, trajectory):
        super().__init__(trajectory)

        # Define constants
        self.lr = 1.39
        self.lf = 1.55
        self.Ca = 20000
        self.Iz = 25854
        self.m = 1888.6
        self.g = 9.81
```

```

# Iter 1: 0.1, 0.0, 0.0
# Iter 2: 0.1143588810000004, 0.0, 0.0178966525
# Iter 3: reducing Kp a bit to reduce oscillations
self.lateral_pid = PID(Kp=0.1, Ki=0.0, Kd=0.0178966525, dt=0.032)

# Iter 1: 29.91, 1.36, 0.03
# Iter 2: 27.580149049219923, 0.4822354299071474, 0.0734521331616762
self.longitudinal_pid = PID(27.580149049219923, 0.4822354299071474,
0.0734521331616762, 0.032)

def update(self, timestep):

    trajectory = self.trajectory

    lr = self.lr
    lf = self.lf
    Ca = self.Ca
    Iz = self.Iz
    m = self.m
    g = self.g

    # Fetch the states from the BaseController method
    delT, X, Y, xdot, ydot, psi, psidot = super().getStates(timestep)

    # -----|Lateral Controller|-----
    # closest node
    cross_track_error, idx = closestNode(X, Y, trajectory)
    closest_node = trajectory[idx]
    next_node = trajectory[(idx + 1) % len(trajectory)] # safe wrap-around

    # Path tangent vector
    t_dx = next_node[0] - closest_node[0]
    t_dy = next_node[1] - closest_node[1]

    # Vector from path to car
    v_dx = X - closest_node[0]
    v_dy = Y - closest_node[1]

    # Signed cross-track error
    signed_cte = np.sign(t_dx * v_dy - t_dy * v_dx) * cross_track_error

    # PID control
    delta = self.lateral_pid.update(0, signed_cte)
    delta = clamp(delta, -np.pi/6, np.pi/6)

```

```
# -----|Longitudinal Controller|-----
# Many of the attempt changes were made by adjusting speed
desired_speed = 10.5
current_speed = np.sqrt(xdot**2 + ydot**2)
F = self.longitudinal_pid.update(desired_speed, current_speed)
F = clamp(F, 0, 15736)

# Return all states and calculated control inputs (F, delta)
return X, Y, xdot, ydot, psi, psidot, F, delta
```