

Vehicle dynamics

Lesson n.1:
Fundamentals

Outline

- Introduction
- Vehicle dynamics in general
- Lumped parameter modelling
- Reference frames
- Fundamentals of rigid-body dynamics

Introduction

VEHiCLE DYNAMICS

Naval



Aerospace



Rail



Road vehicles



Tires → control forces
at road-tire interface
patches

Scope of the course

Core components and simulation (predictive) models

Longitudinal dynamics

- Acceleration
- Braking

Vertical dynamics

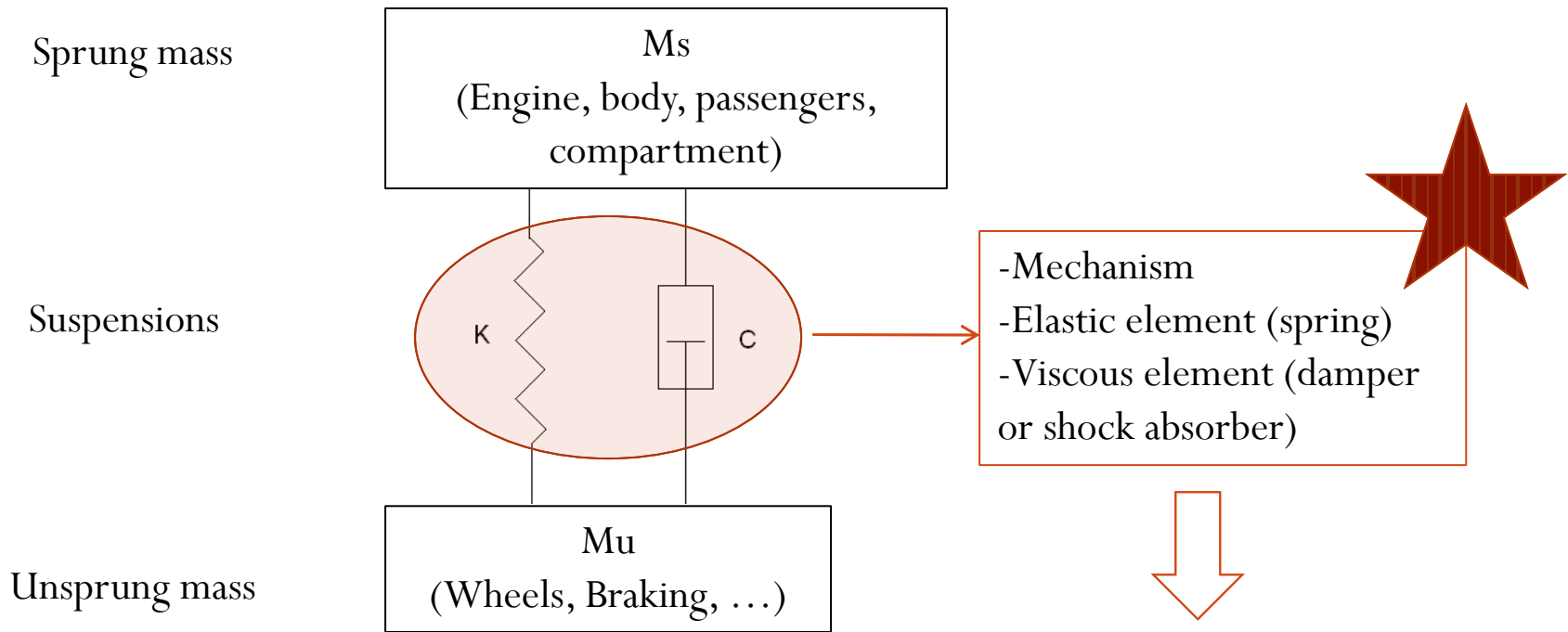
- Ride ($f < 50$ Hz)
- Noise ($50 \text{ Hz} < f < 20 \text{ kHz}$)

Lateral dynamics

- Handling
- Manoeuvring

- Reference frames
- Suspensions
- Tire-road contact

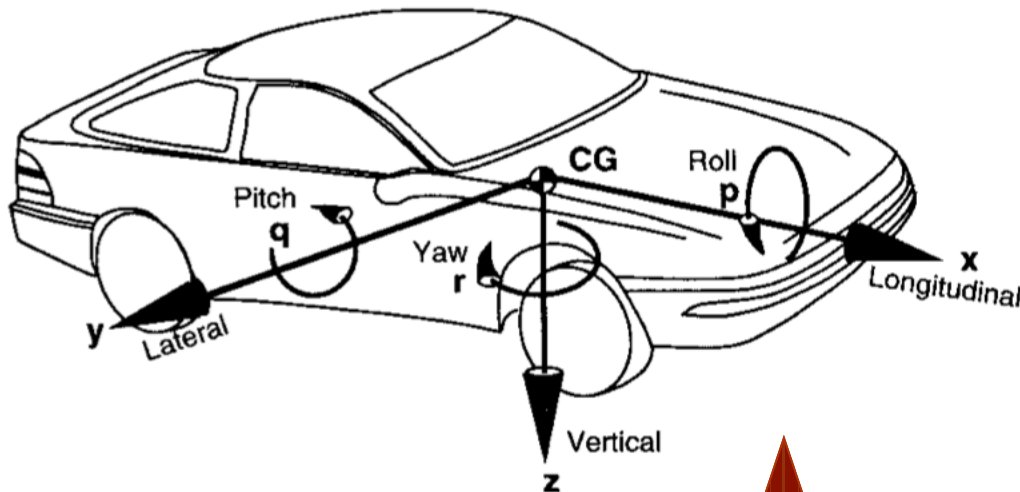
Lumped parameter modelling



1. Control forces transfer from tire-road contact patches to vehicle body
2. Comfort for passengers and goods

Vehicle reference frame

SAE Vehicle axis system



- CG Centre of Gravity
- x-axis: longitudinal, forward
- y-axis: lateral, pointing to the left
- z-axis: vertical, aligned with g

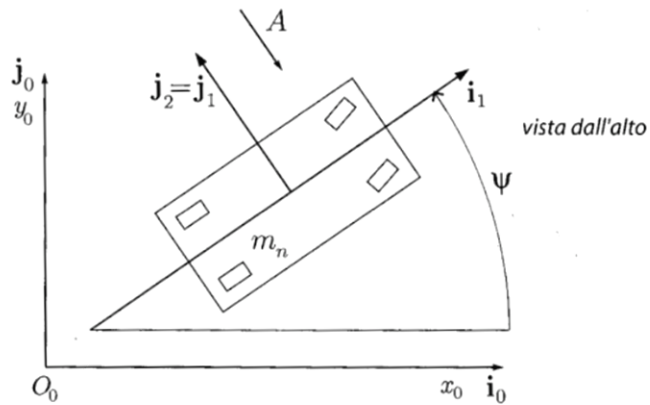
Generalized coordinates:

- displacement along x
- displacement along y
- displacement along z
- Rotation p around x-axis
- Rotation q around y-axis
- Rotation r around z-axis

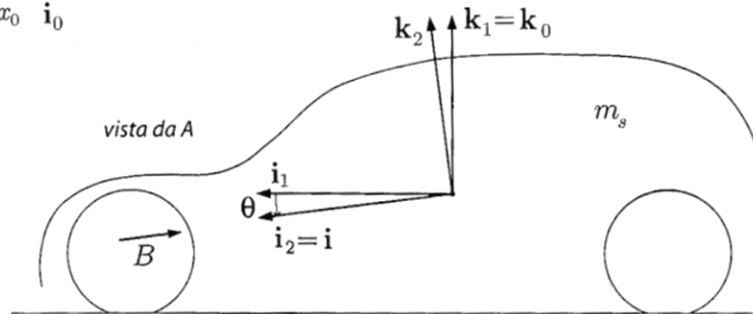
- Roll (moto di rollio)
- Pitch (moto di beccheggio)
- Yaw (moto di imbardata)

Earth-fixed axis system

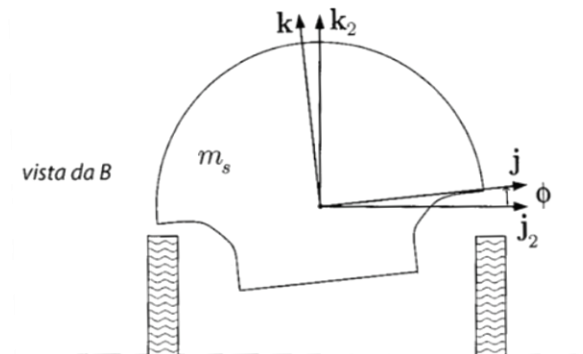
SAE Earth-fixed axis system



- x_0 -axis: forward direction
- y_0 -axis: lateral direction
- z_0 -axis: vertical direction, aligned with $-g$

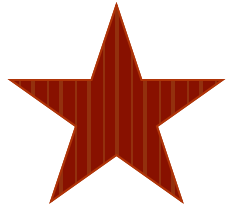


- Yaw
- Pitch
- Roll



Rigid-body dynamics

D'Alembert's Principles:



$$\sum F_x = M \cdot a_x$$

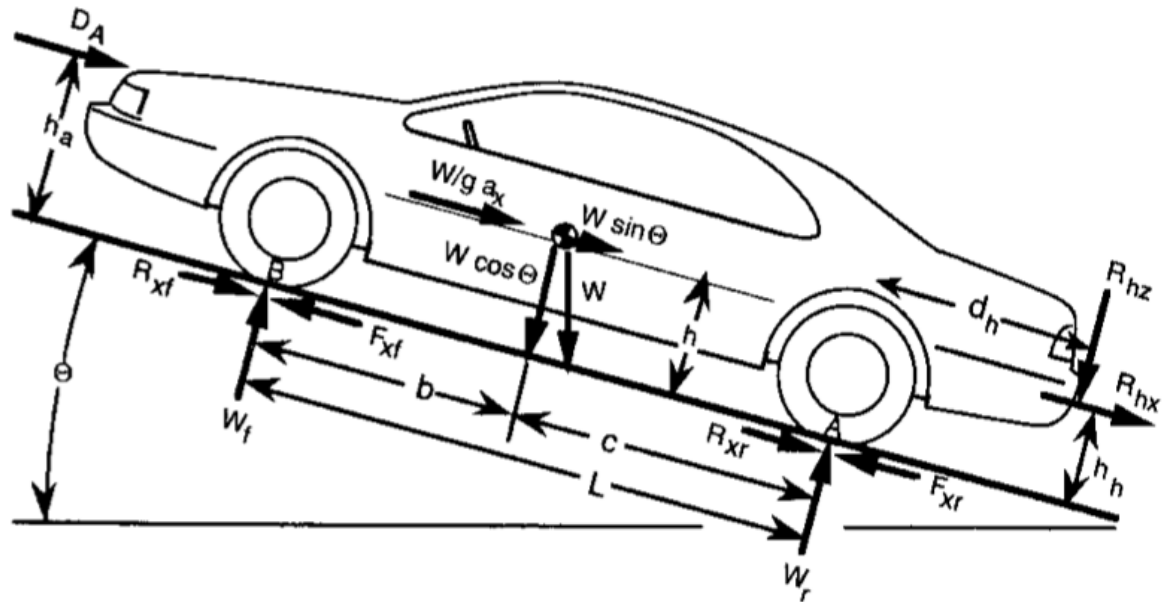
(1-directional motion)

$$\sum T_x = I_{xx} \cdot \alpha_x$$

(Planar motion)

Application example:

Hp: steady-state
conditions (no pitching)



Let's compute

W_f e W_r to understand the following:

- How the static load is distributed between front and rear axle (W_{fs} e W_{rs})
- How the road grade affects the load transfer
- How the acceleration affects the load transfer