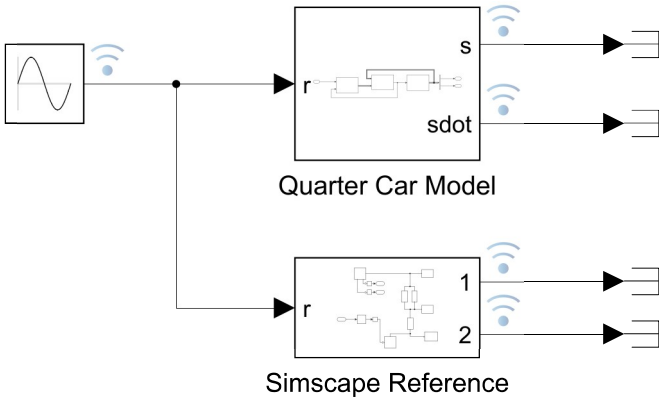
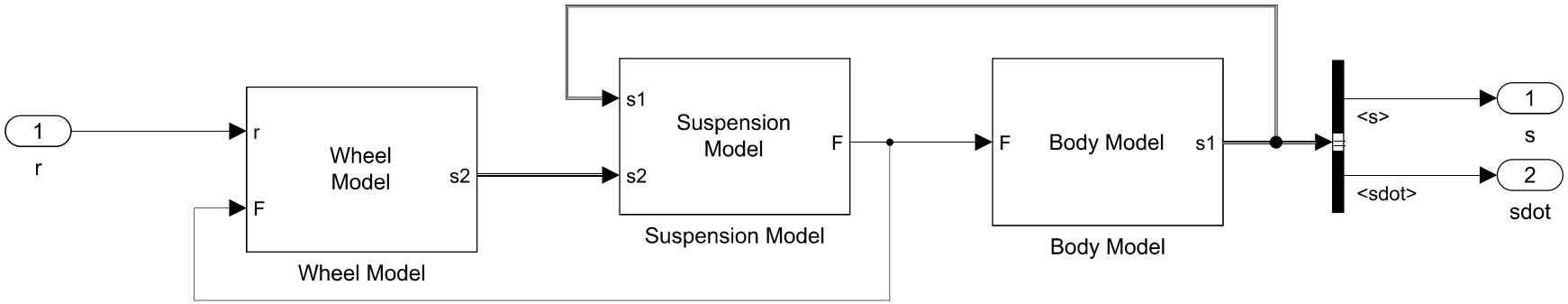
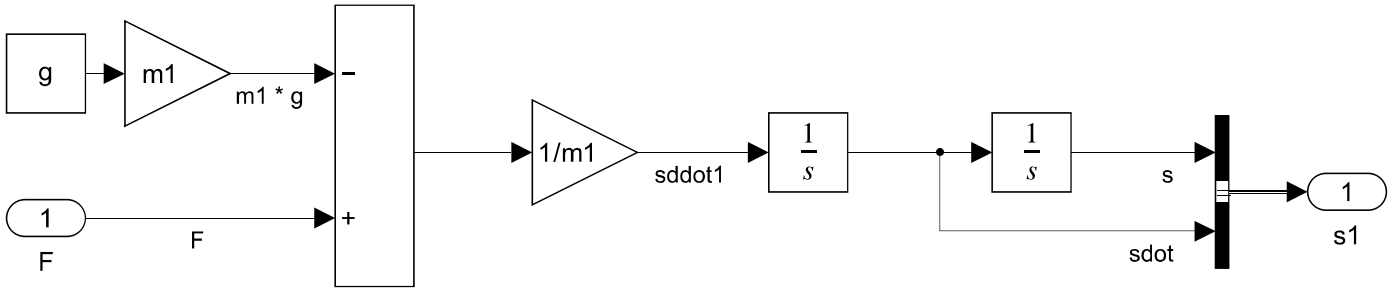
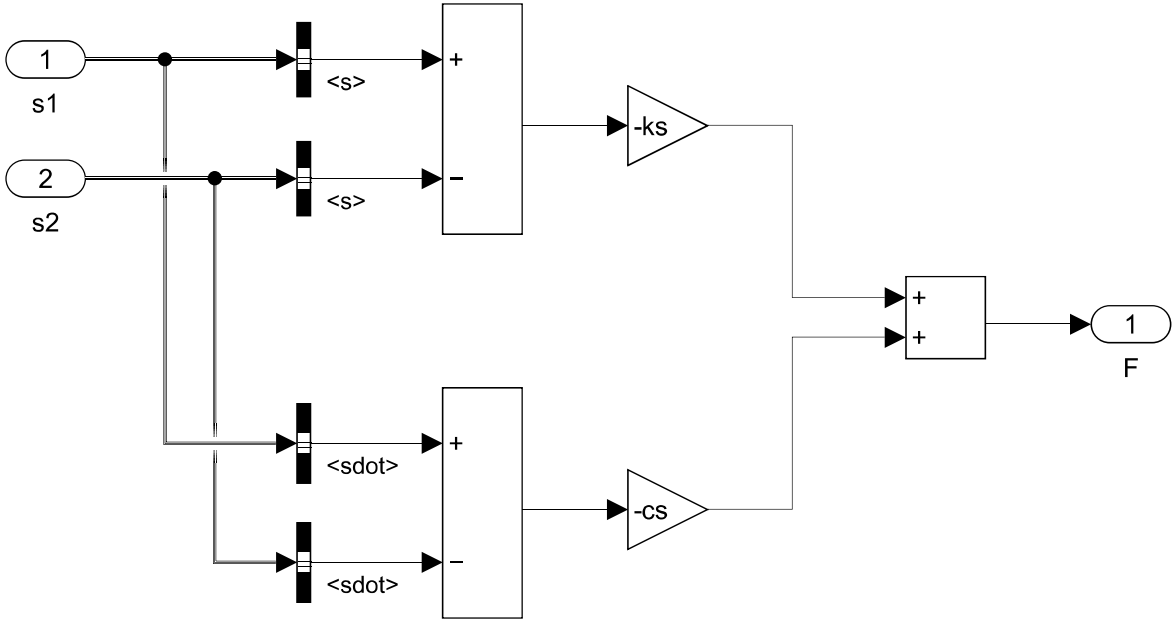

s
r
sdot
Quarter Car Model
1
r
2
Simscape Reference

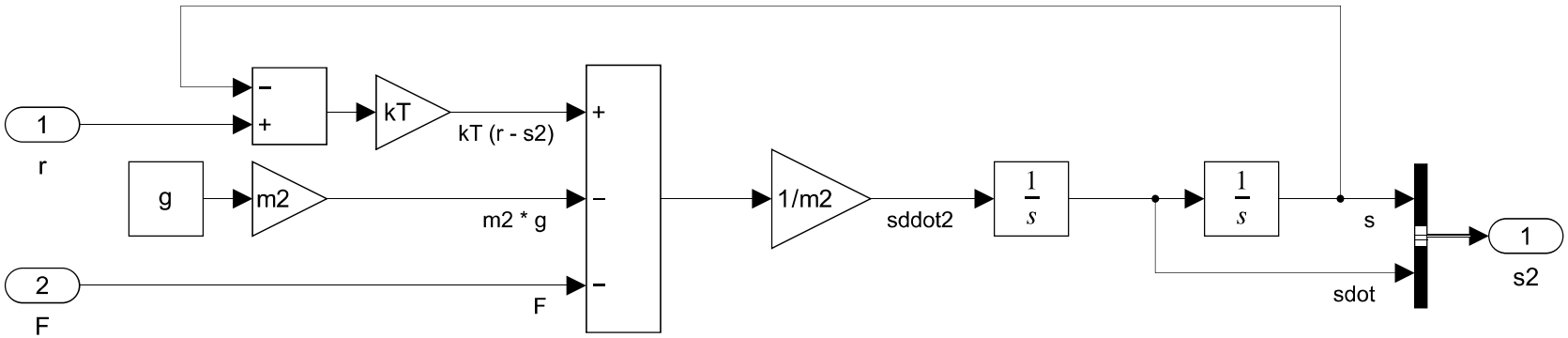

1
r
r
F
Wheel
Model
s2
Wheel Model
s1
s2
Suspension
Model
F
Suspension Model
F
Body Model
s1
Body Model
<s>
<sdot>
1
s
2
sdot



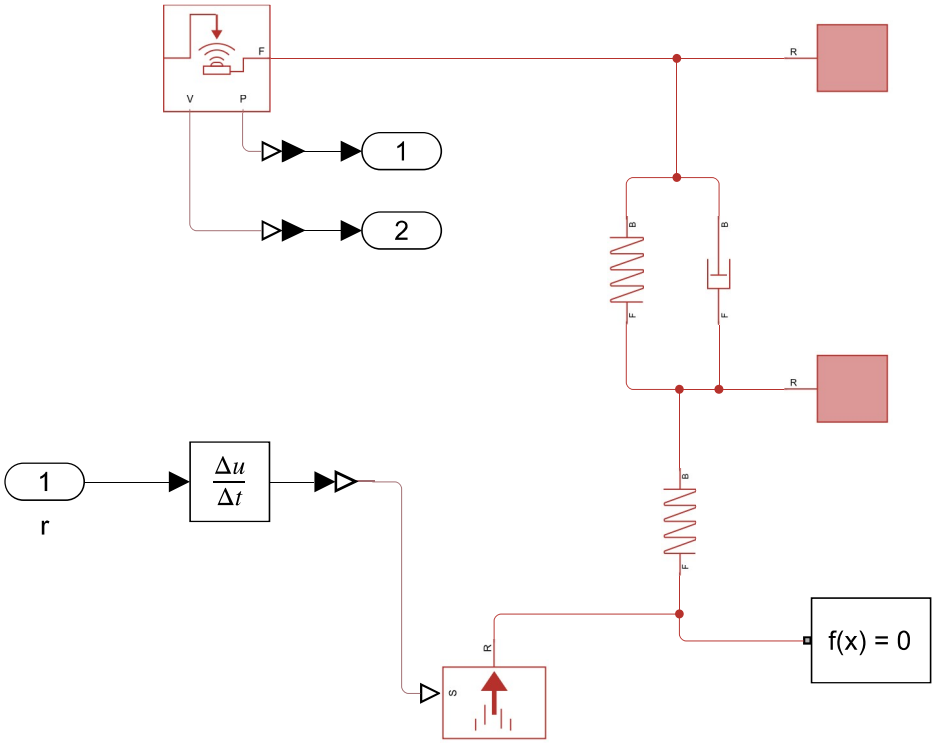
m1 * sddot1 = F - (m1 * g)



F = -ks(s1 - s2)-cs(sdot1 - sdot2)



m2 sddot2 = -F + kT (r - s2) - (m2 * g)


F
V
P
1
2
R
B
F
B
F
R
1
r
Δu
Δt
B
F
R
S
f(x) = 0