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Control oriented modelling of four wheeled electric vehicles



Advisor:

prof. Andrea Bonci

Candidate:

Sebastian Giles

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Sommario

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Summary

Abstract, in English.

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Chapter 1

Introduction

1.1 Background

1.2 Objectives

1.3 Approach

Chapter 2

Tyres

Tyres are the main source of external forces and moments acting upon any road vehicle[cita milliken race car VD], for this reason, understanding their behaviour is key in making accurate predictions about vehicle dynamics. The tyre is a very complex system exhibiting high non linearities, especially in the wide operating range imposed by racing[trova una fonte]. A realistic model of the road-vehicle interaction is clearly necessary in order to obtain significant results from simulations but the detailed study of tyres is far beyond the objectives of this work. The present chapter provides only the fundamental concepts behind tire modelling needed to introduce the numerical model that was used.

2.1 Tyre modelling basics and definitions

All forces acting between the vehicle and the road are distributed over the surfaces of the so called *tyre contact patches*. As the tyre contact patches size and shape are dependent on the operating conditions [trova fonte], for each wheel, we consider a *tyre contact point*, C , as the point at which an applied vector can approximate all forces acting between the tyre and the road.

Various definitions for this point may be used to include more or less complicated effects due to tyre compliance, such as dynamic caster or centrifugal deformation.[cita un articolo su questi effetti] Modelling of such phenomena would require extensive experimental data and is considered to be outside the scope of this research, thus, the following simplified definition for the tyre contact point was deemed satisfactory. The road is assumed to be a flat and planar surface and the tyre is to be considered as an infinitely thin rigid disk

tangent to this plane. The tangent point will be considered as the tyre contact point.

The wheel co-ordinate system is required for the definition of all the related physical quantities. We consider a reference system [figura] with origin in C , whose x axis lies along the intersection between the road plane and the wheel plane, such that it is generally oriented in the direction of motion, and whose z axis is pointing down, perpendicular to the road plane, the y axis is determined by asserting $Cxyz$ to be a right-handed cartesian coordinate system.

The angle between the xz plane and the tyre plane is known as the camber angle [trova definizione SAE].

The x , y and z axes are respectively associated with the *longitudinal*, *lateral* and *vertical* dimensions of the wheel.

As tyre compliance is neglected in this work, the vertical force F_z acting through the tyre and its contact point is considered as independent of tyre behaviour. This choice also excludes all transient responses of the rubber. The longitudinal and lateral friction forces, F_x and F_y , are to be computed since these are what effectively make the vehicle accelerate and corner and are of primary interest.

Consider a wheel [figura] having radius R and angular velocity ω about its spin axis, passing through the wheel center and orthogonal to the wheel plane. We consider ω as positive when the upper half of the wheel is moving in the positive x direction. The lowest point of the wheel is then moving with velocity $v_w = -\omega R$ in the wheel x direction. By considering the velocity of the point C in a road-fixed reference system and letting v_x and v_y be its projections onto the wheel x and y axes. Clearly the longitudinal velocity of the road with respect to the wheel system is $v_{rx} = -v_x$. It is therefore possible to define the longitudinal slip as the difference between these two velocities at the contact point:

$$v_{sx} = v_w - v_{rx} = v_x - \omega R.$$

We further define the slip ratio as [SAE J670]

$$\kappa = -\frac{v_{sx}}{v_x} = \frac{\omega R}{v_x} - 1.$$

The slip angle α is the angle formed between the contact point velocity vector in the road frame and the wheel x axis. It can be formally defined by the equation

$$\tan \alpha = \frac{v_y}{v_x}.$$

F_x and F_y scale almost linearly with the vertical load exerted on the tyre, for this reason it makes sense to define the longitudinal and lateral friction coefficients as

$$\mu_x = \frac{F_x}{F_z}$$

and

$$\mu_y = \frac{F_y}{F_z}$$

κ and α are the primary variables affecting the friction coefficients and are used to estimate μ_x and μ_y . However, there are other factors that define the steady state tyre behaviour, some of which are relatively straight-forward, such as camber angle, vertical load, wheel rotational velocity, tyre pressure and temperature and others which are extremely difficult to quantify, such as asphalt characteristics, and rubber aging.

The typical correlation between friction coefficients and slip ratio and slip angle is shown in [figure dei coeff di attrito tipo dal Kiencke], ideally, all curves pass through the origin, due to the fact that without slip the speed of the wheel is the same as that of the contact point, and no friction forces can be generated. In reality, there is a slight offset caused by rolling resistance and asymmetric tyre constructions [letto in qualcosa di pacejka].

It is also clearly noticeable that in order to obtain maximum longitudinal traction there will be an optimal amount of slip ratio. Limiting the tractive torque to not exceed this value is the exact purpose of launch control systems.

Another effect of the pneumatic tyre is the so called self aligning torque, this moment is exerted about the tyre z axis and is an important contributor to the steering effort which is applied to the steering wheel, this will be relevant to the steering dynamics introduced in the 12 DoF model presented in Chapter 5.

2.2 Magic Formula tyre models

A series of semi-empirical tyre models was developed during the past 30 years by Hans B. Pacejka of Delft University.

These models are based on the same parametric mathematical expression, nicknamed *Magic Formula* because of the good fitting properties it offers despite the lack of a physical foundation. The general form of these functions is

$$R(k) = d \sin(c \arctan(b(1 - e)k + e \arctan(bk)))$$

where R is the physical quantity to be estimated and k is the most relevant variable whilst d , c , b , e and k are fitting coefficients, which may in turn depend on other variables. The set of equations released in 1996, called *Deft Tyre 96* [riferisci all'articolo 96] was the first to include combined effects of longitudinal and lateral slip, subsequent editions of the model have been conceived to model tyre pressure changes [riferisci all'articolo 2004] and more. The version which has been chosen in this work is the PAC2002 model [riferisci all'URL del pdf online], formalized by MSC Software and released as part of their Adams CAR multibody simulation package, which includes a set of tools for obtaining the fitting coefficients from experimental datasets. The standard file format used for the storage of the tyre coefficients is text based and can also be interpreted by an appropriate MATLAB script [refer to implementation paragraph]. The input variables of this tyre model are the slip ratio, slip angle, vertical force and camber angle. Outputs are the longitudinal and lateral forces and the self aligning torque.

2.3 Tyre Data

Experimental tyre data that is specific to Formula SAE and Formula Student tyres has been gathered by the FSAE Tyre Test Consortium [link al TTC] at the Calspan test facility. The expensive tests are funded by the one-time fee the student teams pay to access the information. As access to experimental data was not possible during the preparation of this work, a sample tyre model was used. As the coefficients were given, the fitting process was not necessary. To verify that the tyre model was consistent with the physical intuitions developed so far, some plots were drawn (shown in [figure fatte in matlab]), these both exhibit a plausible correlation between the slip quantities and the friction forces.

Chapter 3

Common models

3.1 Single Track Model

3.2 *some other model*

Chapter 4

Six degree-of-freedom vehicle model

4.1 6DoF Model structure

The state of the car is identified by the six degrees of freedom required to define the spacial position and orientation of its chassis. The car interacts with the road through a simplified suspension system. The model outputs are the vertical forces on each of the four wheels, calculated as the force in each of the suspension systems and the velocities of the respective ground contact points, which may be used to calculate friction forces by an external tyre model. Inputs to the model are the longitudinal and lateral forces acting on each wheel and the angle of the front wheels which is used to rotate the force vectors acting on them, in order to obtain steering control. The block diagram in [\[figura\]](#) shows the intended flow of information for this model working in conjunction with a tyre model.

4.2 Chassis description

The chassis is represented by a rigid body whose mass and rotational inertia resemble those of the entire vehicle, comprehensive of the driver and the wheels, this body is assumed to be simmetrical about the longitudinal-vertical plane. This eliminates the product of inertia terms between the The road is assumed to be a horizontal plane, so we can define the xyz inertial reference system where z is pointed downwards, in the direction of the gravitational acceleration vector, x and y lie on the road surface and may be arbitrarily

chosen as long as the right-handedness of the reference frame is maintained. When the vehicle is static and in equilibrium we proceed to define the body reference system $x'y'z'$, originated at the Center of Gravity of the chassis: y is directed [SAE J670]

[usare molteplici figure: 1. sistemi di riferimento e coordinate lagrangiane - 2. sospensioni su un solo asse - 3. vista 3d delle sospensioni su una sola ruota - 4. vista 3d dei soli punti di attacco] The rigid body represents all the mass of the vehicle including dri Each spring represents the suspension of one of the wheels, with one end attached to the The springs are constrained in the vertical orientation, but are allowed to slide with the lower end the rigid body represent

4.3 Suspension

4.4 Limitations

While this model benefits from the simplicity of its description The main limitation of this model is the lack of the wheel rotational dynamics, which leads to missing reaction torques present during acceleration and braking.

4.5 6DoF Dynamics equation set

[districare il groviglio che mi lascia Matlab]

Chapter 5

The twelve degree-of-freedom Model

5.1 12DoF Model structure

5.1.1 Inputs and Outputs

5.2 Steering

5.3 Wheels

5.4 Limitations

5.5 12DoF Dynamics equation set

Chapter 6

The Matlab modelling environment

6.1 Why Matlab

6.2 Matrix operations

6.3 Symbolic math toolbox

6.3.1 sym and symfun

6.4 Simulink

6.4.1 Common blocks

6.4.2 Simulation data inspector

6.4.3 Simulation control

6.4.4 Simulink Block Libraries

6.4.5 Block Masks

Chapter 7

Model implementation workflow

7.1 Top level simulation diagram

7.2 Tyre Block

7.2.1 Magic Formula Function

7.2.2 Tyre model parameters

7.3 Vehicle Body Block

7.3.1 Parameters and initial state

Chapter 8

Conclusion

8.1 Future Work

8.1.1 Aerodynamic effects

8.1.2 Driving algorithm

Appendix A

Appendix A - Math

Appendix B

Appendix B - 6DoF Matlab Code

Appendix C

Appendix C - 12DoF Matlab code

Bibliography

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