Sr. No	Author Name	Title	Journal and year	Remarks
6	Subhan Khan et.al	Nonlinear Model Predictive Path Following Controller for a Small-Scale Autonomous Bulldozer for Accurate Placement of Materials and Debris of Masonry In Construction Contexts.	IEEE Access, 2021	**1.** In place of modern predictive control this paper used Nonlinear modern predictive control. **2.** Map-based localizer is implemented by the Extended Kalman Filter (EKF) and for validation the result Husky A-200. **3.** Proposed controller is robust and efficient enough to solve the problem for proper industrial-grade applications.
7	Junjie Zhou et.al	A Novel Heading Predictive Control Model for Autonomous Ground Vehicles.	IEEE Mechatronics and automation, 2016	**1.** The developed approach includes a nonlinear vehicle dynamic model which takes the actual tire side-slip characteristics into account. **2.** The vehicle speed and desired heading angle inputs, also showing the increase tracking error as the vehicle is running at faster or turning more severely.
8	Fang Yang et.al	A Skid-Steering Method for Path Following Control of Distributed Drive Articulated Heavy Vehicles	IEEE Access 2022	**1.** A novel skid steering method (SSM) proposed in this paper in Which hydraulic steering method (HSM) is replaced with a system that differentially controls the driving wheels to improve vehicle steering method. **2.** The novel skid-steering method with direct yaw moments that is used to be sole power source during steering process of distributed-drive articulated heavy vehicles (DAHV) is design to replace the conventional HSM. **3.** With help of SSM in the yaw rate control of one variable section to achieve the steering process for DAHV. **4.** A layered control method is implemented in this paper to improve the robustness of the control system in which is composed for an upper path following controller and a lower skid steering controller combine with the double sliding mode control technique.