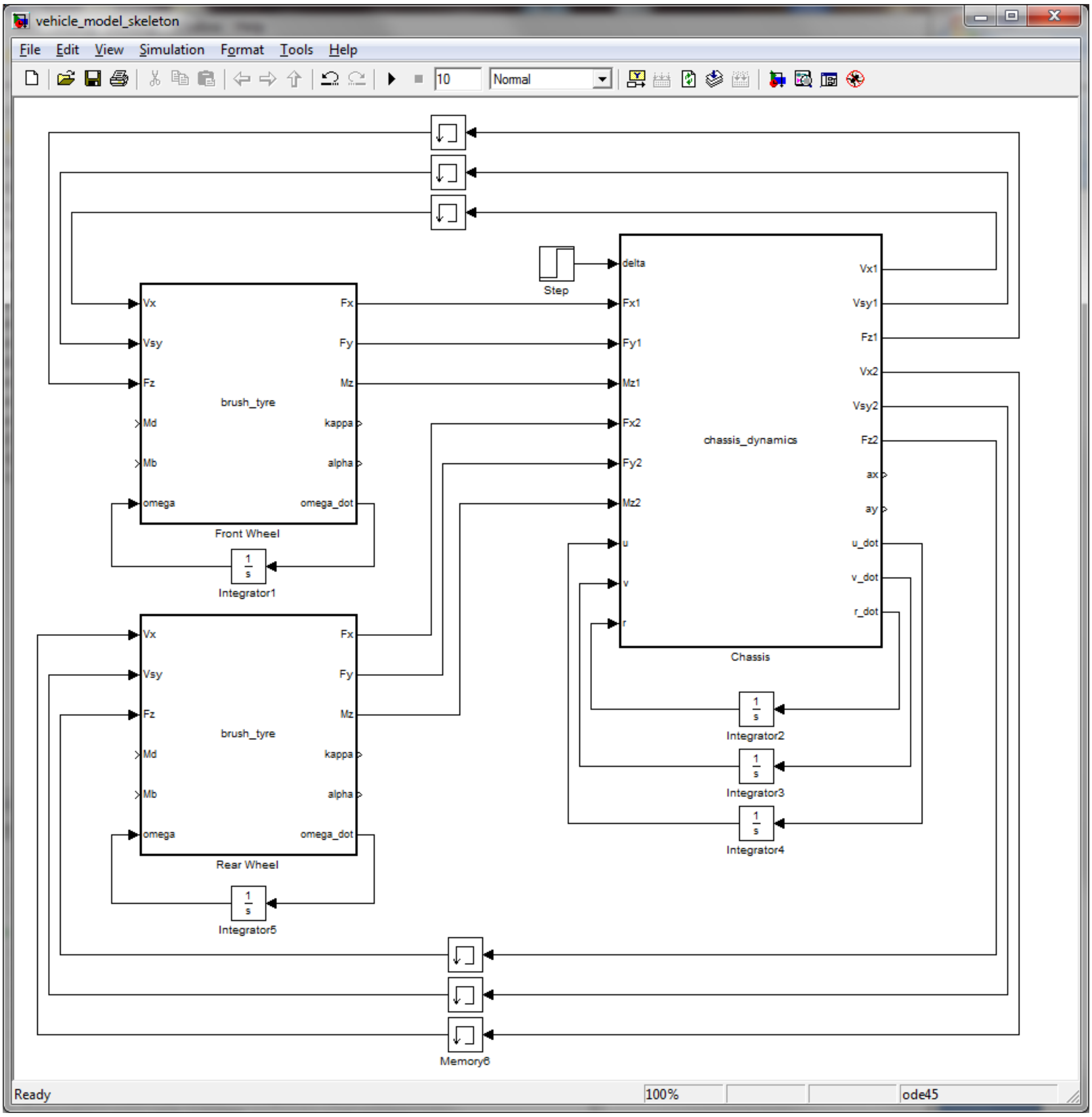
Exercise 4: Non-linear bicycle model (draft)

In this exercise a non-linear bicycle model will be developed using MATLAB/Simulink. The brush model will be used to represent the tyres (you can reuse some of the results of exercise 3).

A Simulink model “vehicle_model_skeleton.mdl” is provided as a starting point. The first task is to enter the right equations in the various Embedded MATLAB function blocks (“Front Wheel”, “Rear Wheel” and “Chassis”). Note that “Front Wheel” and “Rear Wheel” are identical.



First make sure that you can execute a simulation with “vehicle_model_skeleton.mdl”. To be able to do this, a compiler needs to be installed, as described in the document “VD2012_information_v1.pdf”

A description of the in and outputs of each block:

[Fx,Fy,Mz,kappa,alpha,omega_dot]=brush_tyre(Vx,Vsy,Fz,Md,Mb,omega)

inputs

Vx	longitudinal velocity at the wheel centre, in the plane of symmetry of the wheel
Vsy	lateral velocity of the wheel, perpendicular to the wheel plane
Fz	vertical force
Md	drive moment applied to the wheel (see lecture notes, page 181/209)
Mb	brake moment applied to the wheel (see lecture notes, page 181/209)
omega	angular velocity of the wheel

outputs

Fx	longitudinal force
Fy	lateral force
Mz	self aligning moment
kappa	longitudinal slip
alpha	side slip angle
omega_dot	wheel angular acceleration (see lecture notes, page 181/209).

[Vx1,Vsy1,Fz1,Vx2,Vsy2,Fz2,ax,ay,u_dot,v_dot,r_dot] =
chassis_dynamics(delta,Fx1,Fy1,Mz1,Fx2,Fy2,Mz2,u,v,r)

inputs

delta	front wheel steer angle
Fx1	longitudinal force of front tyre (in the wheel frame)
Fy1	lateral force of front tyre (in the wheel frame)
Mz1	self aligning moment of front tyre
Fx2	longitudinal force of rear tyre (in the wheel frame)
Fy2	lateral force of rear tyre (in the wheel frame)
Mz2	self aligning moment of rear tyre
u	longitudinal velocity of the centre of gravity (see lecture notes, page 10)
v	lateral velocity of the centre of gravity
r	yaw velocity

outputs

Vx1	longitudinal velocity of the front wheel (in the wheel plane of symmetry)
Vsy1	lateral velocity of the front wheel (perpendicular to the wheel plane)
Fz1	vertical tyre force front tyre
Vx2	longitudinal velocity of the rear wheel (in the wheel plane of symmetry)
Vsy2	lateral velocity of the rear wheel (perpendicular to the wheel plane)
Fz2	vertical tyre force rear tyre
Ax	longitudinal acceleration
Ay	lateral acceleration
u_dot	time derivative of the longitudinal velocity of the centre of gravity
v_dot	time derivative lateral velocity of the centre of gravity
r_dot	time derivative of the yaw velocity

Both blocks are still empty and the first task is to enter the right set of equations. As a start, the vehicle parameters may be taken from exercise 2 and tyre parameters form exercise 3.