Contents

ACKNOWLEDGMENTS ix

INTRODUCTION xi

CHAPTER 1. DRIVING SIMULATION 1

1.1. Objectives of driving simulation 1
1.2. A short history of driving simulators 3
1.2.1. Fixed-base platforms 3
1.2.2. Platforms with a serial structure 5
1.2.3. Platforms with parallel structure 5
1.2.4. Hybrid structured platforms 10
1.2.5. "Low-cost" generation 14
1.3. Driving simulation objectives 16

CHAPTER 2. ARCHITECTURE OF DRIVING SIMULATORS 19

2.1. Architecture of driving simulators 19
2.2. Motion cueing and haptic feedback 26
2.2.1. The human motion perception system 27
2.2.2. Mathematical description 30
2.2.3. Motion cueing algorithm 33

2.3. The evolution of simulators: from the automobile to the motorcycle 48
2.3.1. Honda simulators 48
2.3.2. Tokyo university simulator 51
2.3.3. MORIS simulator 52
2.3.4. SafeBike simulator 53
2.3.5. Bicycle simulator – Kaist 55
2.3.6. Discussion 55

CHAPTER 3. DYNAMICS OF TWO-WHEELED VEHICLES . 57

3.1. Modeling aspect 57
3.1.1. Vehicle motion 59
3.1.2. Road–tire interface 60
3.1.3. Direction system 65
3.1.4. Suspensions 67
3.1.5. Motorization and traction chain 67
3.2. The literature on existing models 69
3.2.1. Models of the automobile 69
3.2.2. Two-wheeled vehicle models 71
3.3. Dynamic behavior of automobiles 77
3.4. Dynamic behavior of two-wheeled vehicles 77
3.5. Summary 82

CHAPTER 4. TWO-WHEELED RIDING SIMULATOR: FROM DESIGN TO CONTROL 85

4.1. Introduction 85
4.2. The design and mechanical aspects of the simulator . . 86
4.3. The mechatronics of the simulator 92
4.3.1. Description of the simulation loop 92
4.3.2. Platform instrumentation 94
4.3.3. Sequencing and synchronization 99
4.4. Specification of the simulator 101
4.4.1. Inverse kinematic of the simulator platform 101
4.4.2. Dynamic modeling of the platform 107
4.4.3. Identification 109

4.5. Multi-sensory integration: washout and force feedback 116
4.5.1. Localization of the washout 116

BIBLIOGRAPHY 125

INDEX 135