

# Contents

Abstract	III
Kurzfassung	V
Nomenclature	IX
<b>1 Introduction</b>	<b>1</b>
1.1 State of the Art	1
1.1.1 Driver Assistance Systems	1
1.1.2 Environmental Sensors	2
1.1.3 Human Machine Interaction	4
1.1.4 Vehicle Guidance Control	6
1.1.5 Motion Planning	8
1.2 Thesis Contributions and Outline	14
<b>2 Lateral Vehicle Dynamics</b>	<b>17</b>
2.1 Reference Frames and Geometry	17
2.2 Tire Modeling	19
2.2.1 Tire Kinematics	19
2.2.2 Tire Forces: The Dugoff Model	21
2.3 Double-Track Model	26
2.3.1 Kinematics	26
2.3.2 Dynamics	27
2.4 Single-Track Model	29
2.4.1 Kinematics	30
2.4.2 Dynamics	31
2.5 Linear Single-Track Model	32
2.5.1 Vehicle-Fixed Formulation	33
2.5.2 Trajectory-Fixed Formulation	34
2.6 Steering Characteristics	36
2.6.1 Ackermann Steering	36
2.6.2 Self Steering Gradient	37
2.7 Model Validation with Experimental Data	41
2.7.1 Steady State Cornering Maneuver	43
2.7.2 Unsteady Cornering Maneuver	45
<b>3 Potential Field based Motion Planning</b>	<b>49</b>
3.1 Hazard Map	52
3.1.1 Road	52
3.1.2 Obstacles	56
3.1.3 Hazard Map Composition	60

3.2	Elastic Band . . . . .	62
3.2.1	Equilibrium Configuration . . . . .	62
3.2.2	Node Placement . . . . .	65
3.2.3	Constraining Longitudinal Displacements . . . . .	65
3.3	Cooperative Motion Planning . . . . .	65
3.3.1	Driver's Steering Intention . . . . .	66
3.3.2	Vehicle State Extrapolation . . . . .	67
3.3.3	Driver's Maneuver Strategy . . . . .	68
3.4	Algorithm and Computation . . . . .	68
3.4.1	Distance Computation . . . . .	68
3.4.2	Initial Solution . . . . .	70
3.4.3	Equilibrium Solution . . . . .	72
3.5	Simulations . . . . .	76
3.5.1	Scenario I: Entering Traffic . . . . .	76
3.5.2	Scenario II: Crossing Animal . . . . .	78
3.5.3	Scenario III: Passing Maneuver with Oncoming Traffic . . . . .	80
3.5.4	Pseudo Code of Motion Planning Algorithm . . . . .	81
<b>4</b>	<b>Potential Field based Vehicle Guidance Control</b>	<b>83</b>
4.1	General Concept of Potential Field Guidance . . . . .	83
4.2	Mapping a Virtual Guidance Force on Control Inputs . . . . .	85
4.2.1	Nonlinear Mapping . . . . .	85
4.2.2	Linear Mapping . . . . .	86
4.3	Path Tracking Error . . . . .	87
4.4	Guidance Kinematics . . . . .	89
4.5	Guidance Dynamics . . . . .	92
4.6	Stability Analysis and Controller Design . . . . .	93
4.6.1	Lyapunov's Direct Method . . . . .	93
4.6.2	Stability Analysis . . . . .	94
4.6.3	Steady State Tracking Error . . . . .	97
4.6.4	A Bound on the Tracking Error - Collision Avoidance . . . . .	97
4.6.5	Sample Controller Design . . . . .	99
4.6.6	Feedforward Control . . . . .	101
4.7	Simulations . . . . .	103
4.8	Comment on Human Vehicle Guidance . . . . .	106
<b>5</b>	<b>Shared Vehicle Guidance between Driver and Assistance System</b>	<b>107</b>
5.1	Vehicle Guidance Control Loop . . . . .	107
5.2	Driving Simulator Exploration . . . . .	109
5.2.1	Haptic Human Machine Interface . . . . .	109
5.2.2	Driving Simulator Setup . . . . .	111
5.2.3	Lane-Keeping and Collision Avoidance Experiments . . . . .	113
5.2.4	Results and Discussion . . . . .	118
<b>6</b>	<b>Conclusion</b>	<b>123</b>
6.1	Summary . . . . .	123
6.2	Future Work . . . . .	124
	<b>Appendix</b>	<b>125</b>
	<b>Bibliography</b>	<b>129</b>