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**REAL-TIME AND HIGH-FIDELITY SIMULATION ENVIRONMENT FOR  
AUTONOMOUS GROUND VEHICLE DYNAMICS**

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**ABSTRACT**

*Integrated simulation capabilities that are high-fidelity, fast, and have scalable architecture are essential to support autonomous vehicle design and performance assessment for the U.S. Army's growing use of unmanned ground vehicles (UGV). The HMMWV simulation described in this paper embodies key features of the real vehicle, including a complex suspension and steering dynamics, wheel-soil models, navigation, and control. This research uses advanced multibody techniques such as minimal coordinate representations with constraint embedding to model complex unmanned ground vehicles for fast mechanical simulations with high fidelity. In this work, we demonstrate high-fidelity dynamics models for autonomous UGV simulations in near real time that can be useful to the U.S. Army for future autonomous ground vehicle dynamics modeling and analysis research.*

**INTRODUCTION**

With increased onboard autonomy, advanced vehicle models are needed to analyze and optimize control design and sensor packages over range of urban and off-road scenarios. Moreover, integrated simulation capabilities that are high-fidelity, fast, and have scalable architecture are essential to support autonomous vehicle design and performance assessment for the U.S. Army's growing use of unmanned ground vehicles.

Recent work at TARDEC has attempted to develop a high-fidelity mobility simulation of an autonomous vehicle in an off-road scenario using integrated sensor, controller, and multi-body dynamics models [1]. The conclusion was that (a) real-time simulation was not feasible due to the complexity of the intervening formulation, (b) models had to be simplified to speed up the simulation, (c) interfacing the sensors was exceedingly difficult due to co-simulation, (d) the controls developed were very basic and could not be optimized, and (e) a rigid terrain model was used.

The JPL ROAMS ground vehicle simulation framework is based on the JPL Darts/Dshell simulation architecture [2], [3], [4], [5]. ROAMS and the underlying architecture have been successfully demonstrated at JPL in several space mission-critical scenarios where a high degree of mission

complexity, real-time performance, and extensive sensor/actuator/control integration were necessary. The underlying framework has been applied to a variety of mission-critical simulation needs for NASA missions across multiple domains (cruise/orbiter, landers, and rovers) over the years. The architecture has supported real-time embedded hardware-in-the-loop use to large-scale Monte Carlo based parametric studies. For further information about the ROAMS, please visit the JPL DARTS Lab website: <http://dartslab.jpl.nasa.gov>.

ROAMS is unique in its integrated approach to straddling the multi-function high-fidelity dynamics, sensors, environment, control, and autonomy models that are key attributes of future Army unmanned ground vehicles (UGVs). This project will facilitate the transfer of this technology to TARDEC so that customers such as RS JPO and DARPA can be supported.

This project is a pilot effort to demonstrate the application of the ROAMS modeling approach for addressing the fidelity and speed bottlenecks for TARDEC and the Army's needs for the evaluation and testing of autonomous ground vehicles. The simulation architecture represents a shift in paradigm in empowering analysts with full visibility and control in tailoring key elements of the simulator. This

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[The Control Handbook](#) William S. Levine, 2018-10-08 At publication The Control Handbook immediately became the definitive resource that engineers working with modern control systems required Among its many accolades that first edition was cited by the AAP as the Best Engineering Handbook of 1996 Now 15 years later William Levine has once again compiled the most comprehensive and authoritative resource on control engineering He has fully reorganized the text to reflect the technical advances achieved since the last edition and has expanded its contents to include the multidisciplinary perspective that is making control engineering a critical component in so many fields Now expanded from one to three volumes The Control Handbook Second Edition organizes cutting edge contributions from more than 200 leading experts The second volume Control System Applications includes 35 entirely new applications organized by subject area Covering the design and use of control systems this volume includes applications for Automobiles including PEM fuel cells Aerospace Industrial control of machines and processes Biomedical uses including robotic surgery and drug discovery and development Electronics and communication networks Other applications are included in a section that reflects the multidisciplinary nature of control system work These include applications for the construction of financial portfolios earthquake response control for civil structures quantum estimation and control and the modeling and control of air conditioning and refrigeration systems As with the first edition the new edition not only stands as

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