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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

# Real Time And High Fidelity Simulation Environment For

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Simulation, Modeling, and Programming for Autonomous Robots Noriako Ando, Stephen Balakirsky, Thomas Hemker, Monica Reggiani, Oskar von Stryk, 2010-11-11 Why are the many highly capable autonomous robots that have been promised for novel applications driven by society industry and research not available day despite the tremendous progress in robotics science and systems achieved during the last decades Unfortunately steady improvements in specific robot abilities and robot hardware have not been matched by corresponding robot performance in real world environments This is mainly due to the lack of advancements in robot software that master the development of robotic systems of ever increasing complexity In addition fundamental open problems are still awaiting sound answers while the development of new robotics applications suffers from the lack of widely used tools libraries and algorithms that are redesigned in a modular and performant manner with standardized interfaces Simulation environments are playing a major role not only in reducing development time and cost e.g. by systematic software or hardware in the loop testing of robot performance but also in exploring new types of robots and applications However their use may still be regarded with skepticism Seamless migration of code using robot simulators to real world systems is still a rare circumstance due to the complexity of robot world sensor and actuator modeling These challenges drive the quest for the next generation of methodologies and tools for robot development The objective of the International Conference on Simulation Modeling and Programming for Autonomous Robots SIMPAR is to offer a unique forum for these topics and to bring together researchers from academia and industry to identify and solve the key issues necessary to ease the development of increasingly complex robot software

*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

a record of accomplishment in control engineering but provides researchers with the means to make further advances Progressively organized the other two volumes in the set include Control System Fundamentals Control System Advanced Methods

**Contemporary Solutions for Sustainable Transportation Practices** Munuhwa, Shakerod, 2024-08-01

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*Program Solicitation*, 1997

**Intelligent Autonomy of UAVs** Yasmina Bestaoui Sebbane, 2018-03-14

Intelligent Autonomy of UAVs Advanced Missions and Future Use provides an approach to the formulation of the fundamental task typical to any mission and provides guidelines of how this task can be solved by different generic robotic problems As such this book aims to provide a systems engineering approach to UAV projects discovering the real problems that need to be resolved independently of the application After an introduction to the rapidly evolving field of aerial robotics the book presents topics such as autonomy mission analysis human UAV teams homogeneous and heterogeneous UAV teams and finally UAV UGV teams It then covers generic robotic problems such as orienteering and coverage The book next introduces deployment patrolling and foraging while the last part of the book tackles an important application aerial search tracking and surveillance This book is meant for both scientists and practitioners For practitioners it presents existing solutions that are categorized according to various missions surveillance and reconnaissance 3D mapping urban monitoring precision agriculture forestry disaster assessment and monitoring security industrial plant inspection etc For scientists it provides an overview of generic robotic problems such as coverage and orienteering deployment patrolling and foraging search tracking and surveillance The design and analysis of algorithms raise a unique combination of questions from many fields including robotics operational research control theory and computer science

**NASA Technical Paper**, 1985

*Human Computer Interaction Handbook* Julie A. Jacko, 2012-05-04

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