



MOTORIST Simulator

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Project Leader – 3D RTD CAE

Group Manager – 3D RTD CAE

MOTORcycle Rider Integrated SafeTy MOTORIST

SIEMENS

Enhance Motorcycle Rider Safety

Motorcycles are an efficient and flexible transport system in the congested European cities. But the risk for the riders is still higher than for other vehicles.

➔ Reduce number of accidents and consequent injuries



**WP1:
Rider
Training**

Improving rider's skills with training strategies both in real and virtual environment

ESR1.2: Maria Di Gesu

**WP2:
Integrated
Safety**

Developing advanced safety systems modelling the rider and the interaction with the motorcycle

ESR2.1: Marco Grotoli
ESR2.3a: Francesco Celiberti

**WP3:
Protective
Equipment**

Developing personal protective equipment

Consortium:



SIEMENS



Associated Partners:

TNO innovation for life

Supervisory Board:

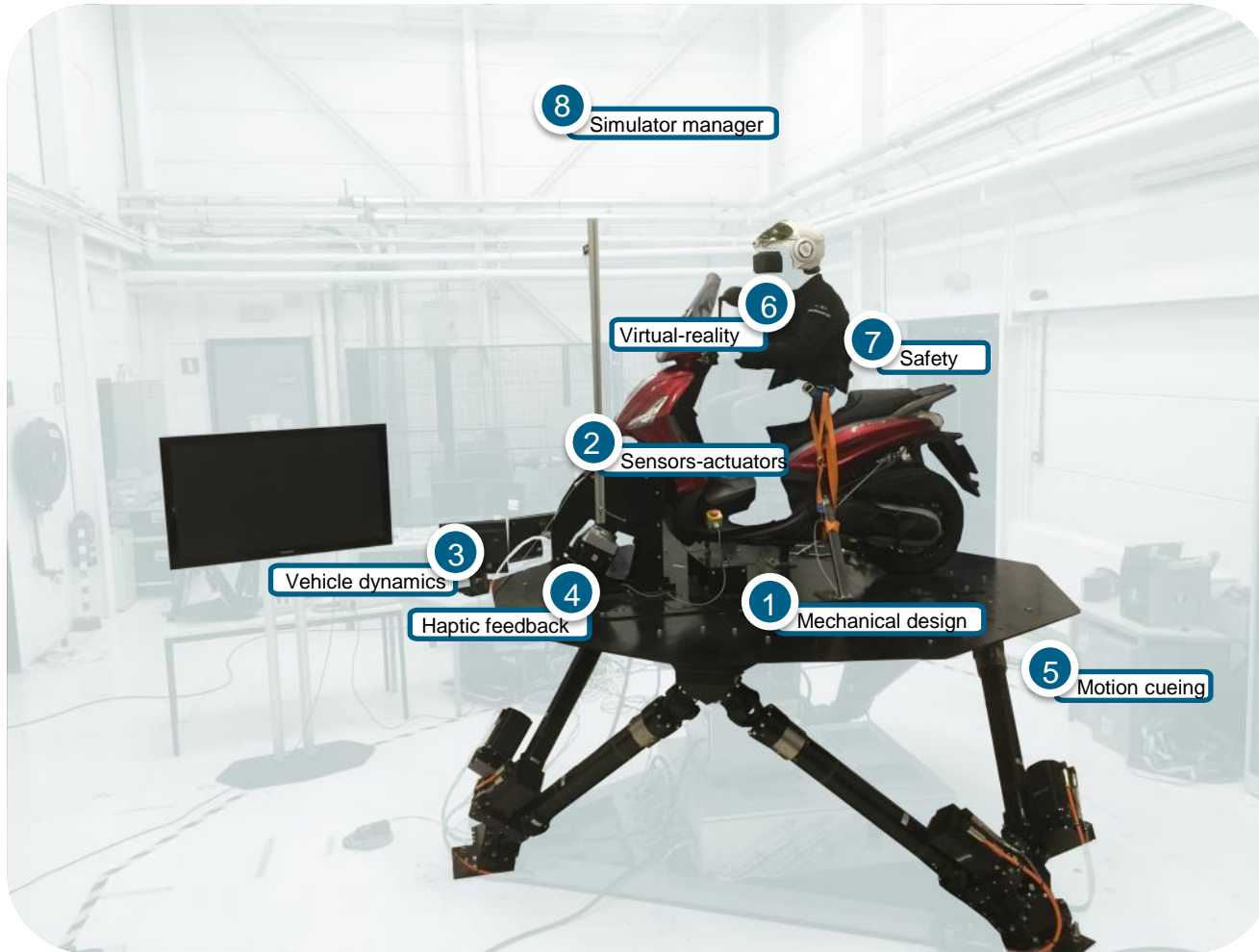


MOOG



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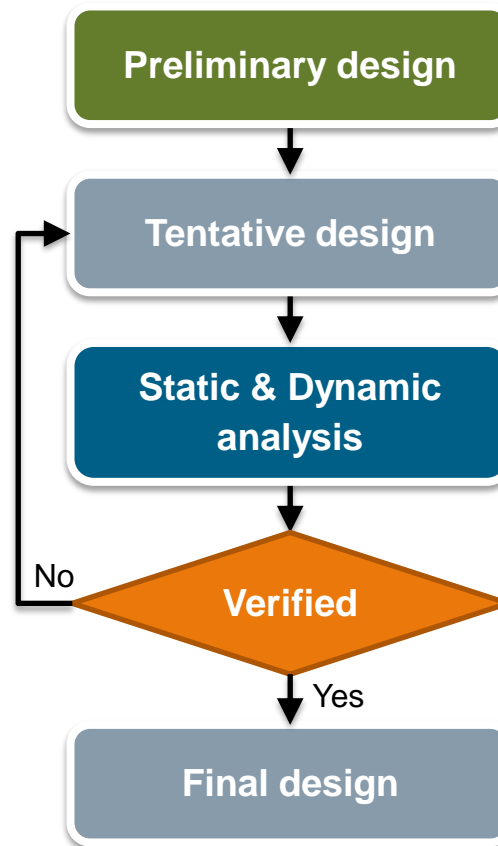
MOTORIST simulator: overview



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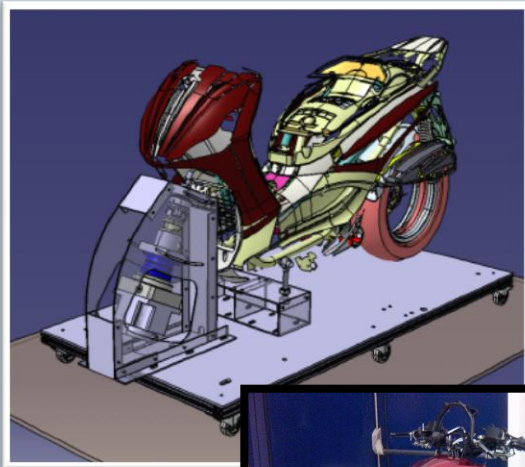


Mechanical Design

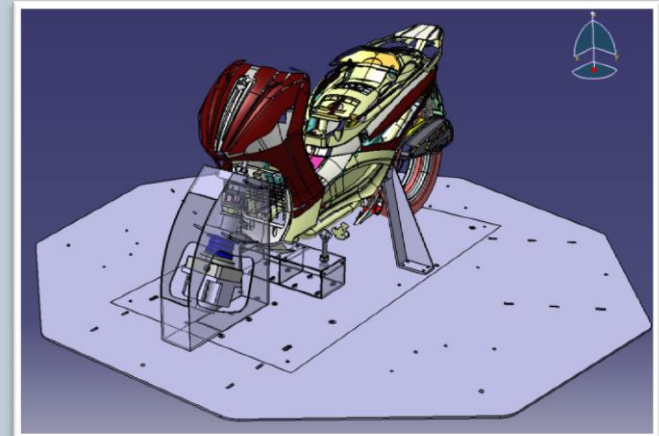
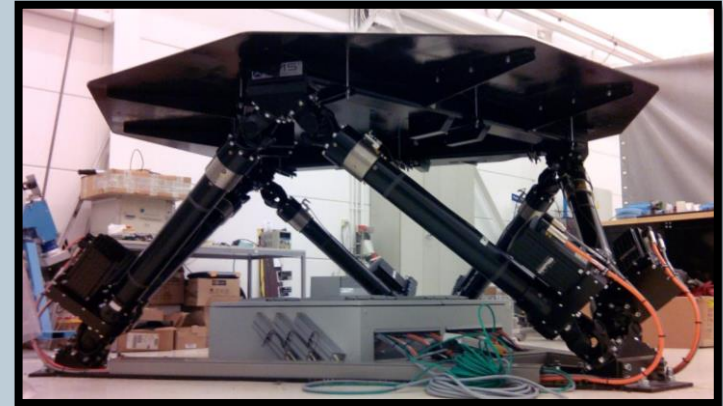


Mechanical Design

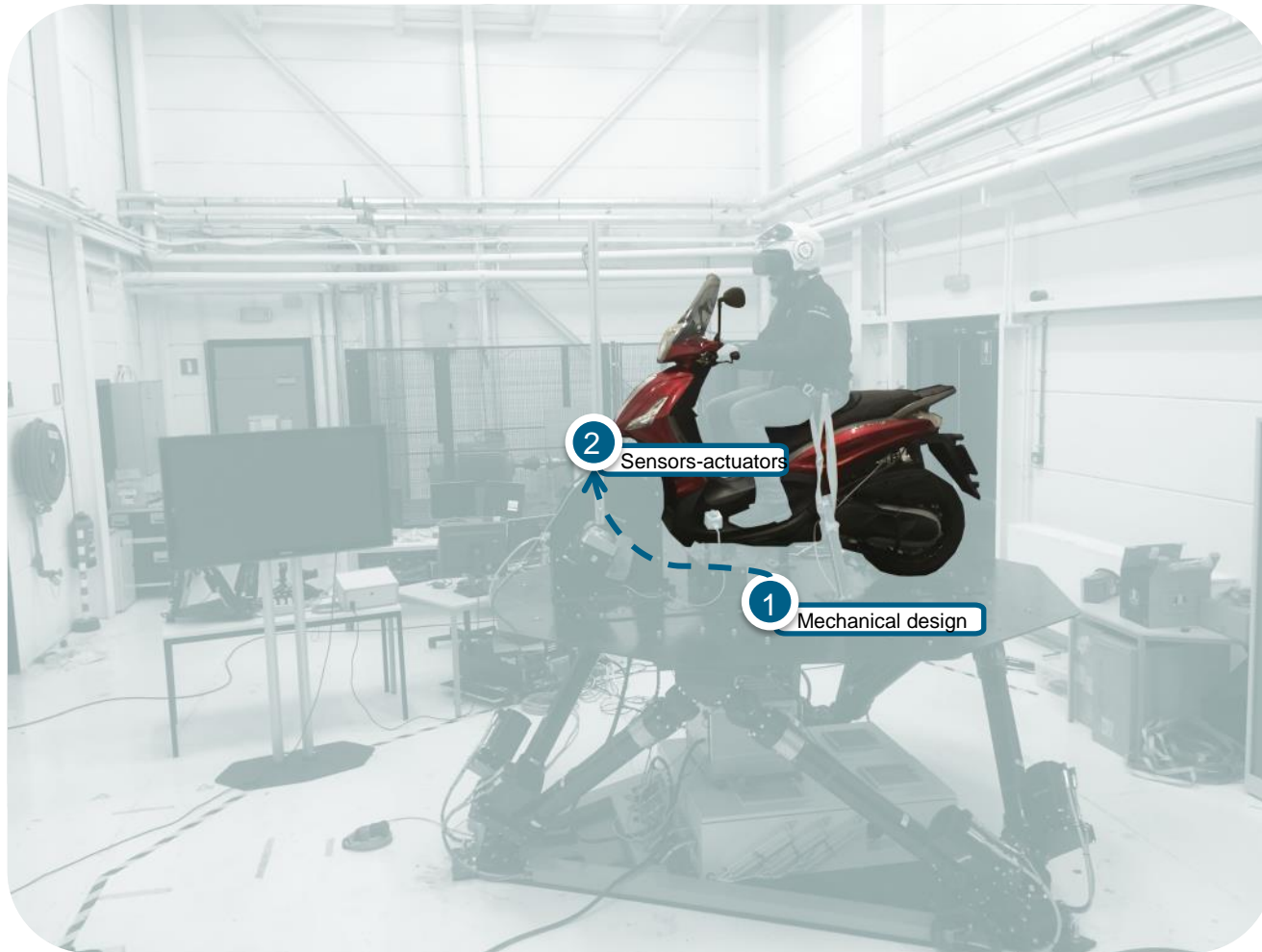
Static setup



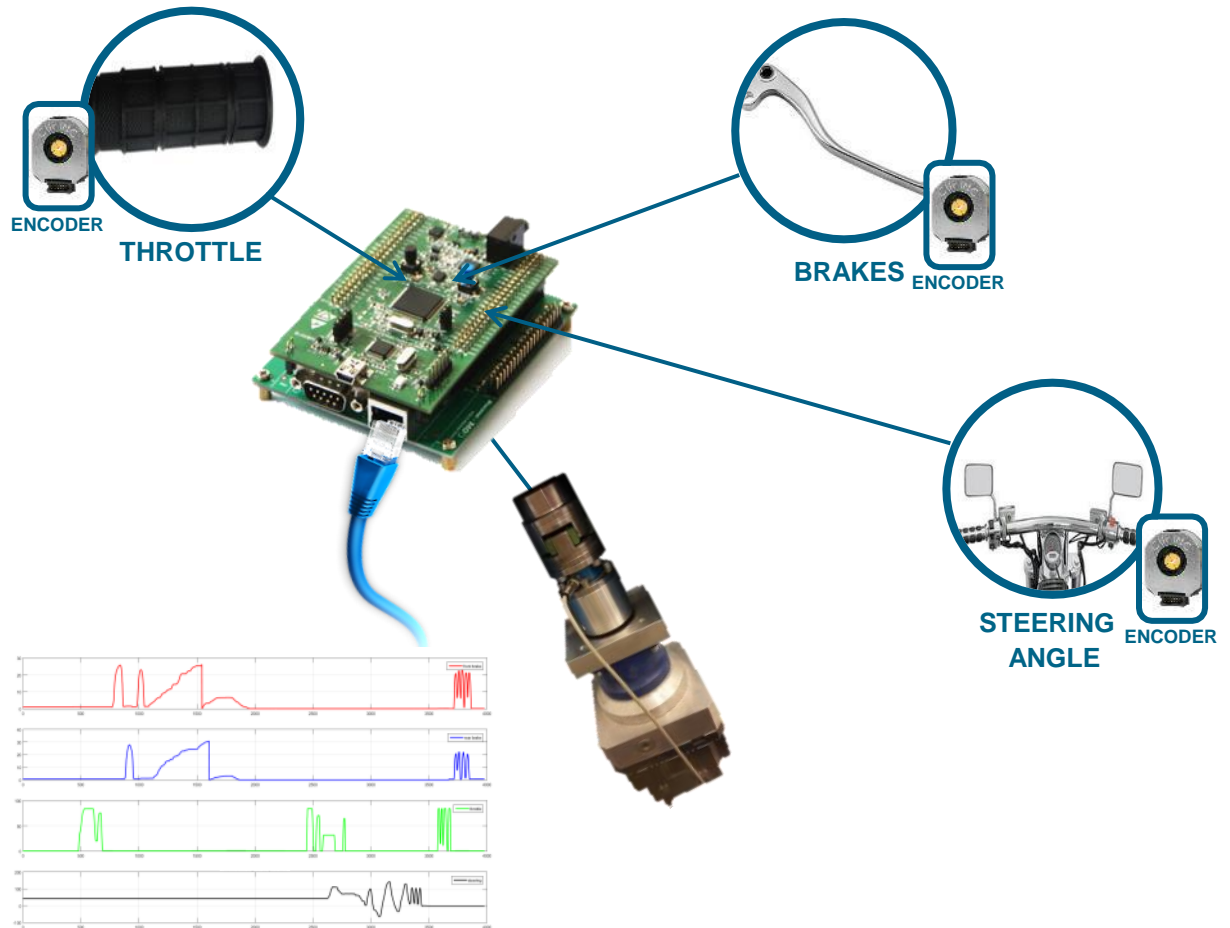
Dynamic setup



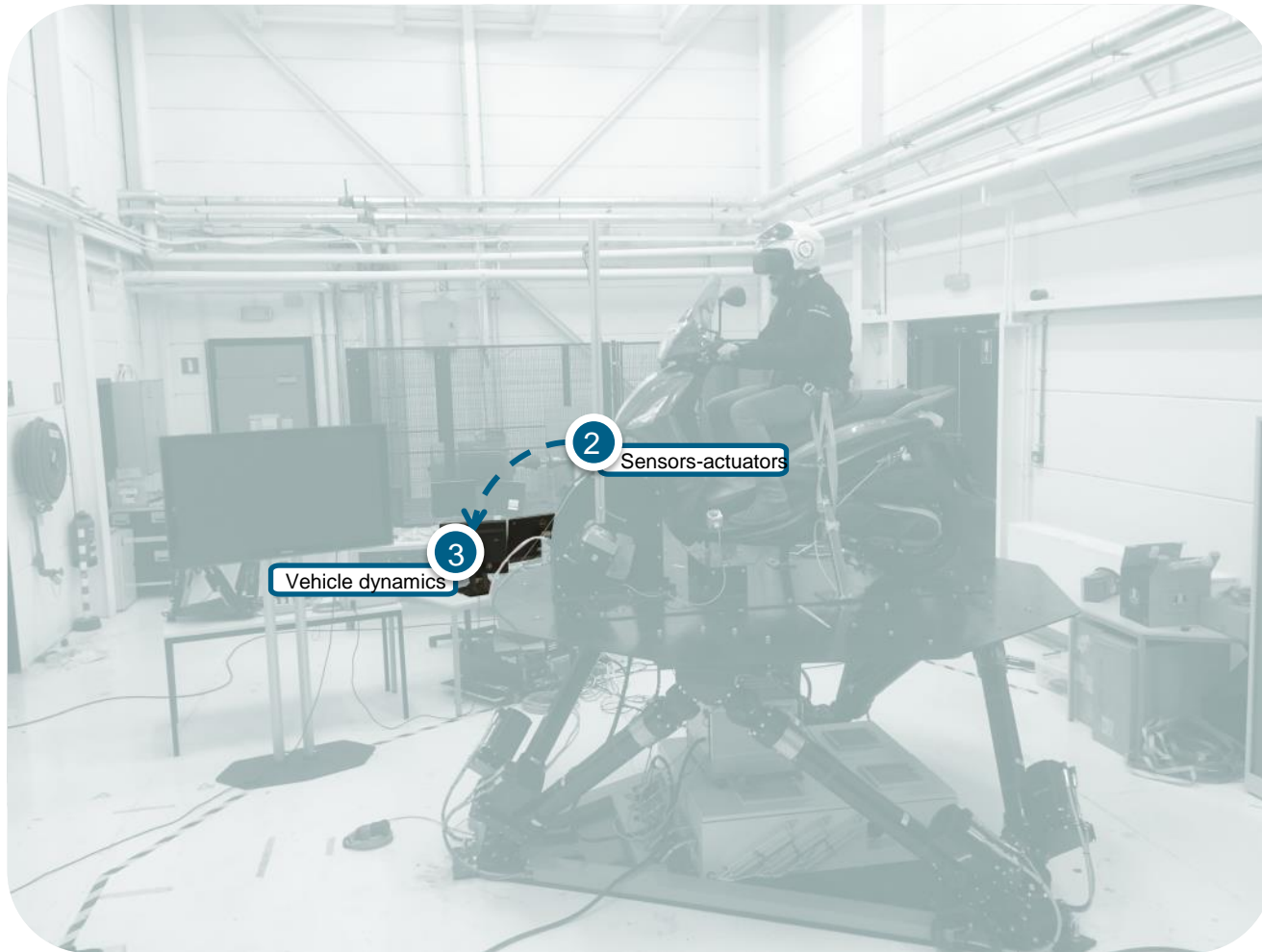
MOTORIST simulator: overview



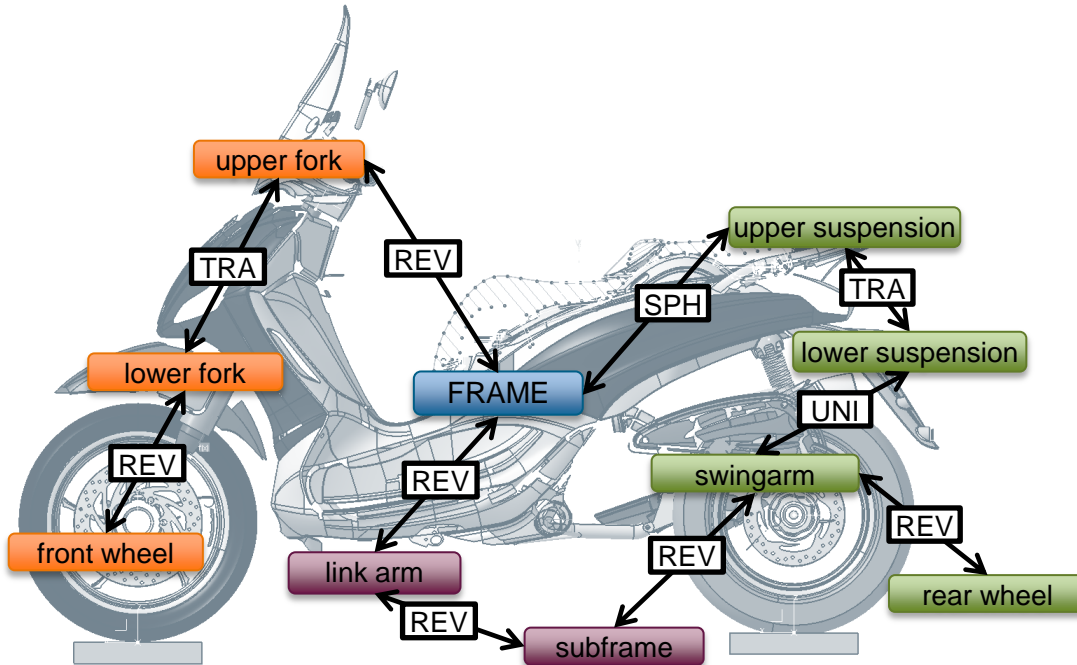
Instrumentation



MOTORIST simulator: overview



Multibody Model



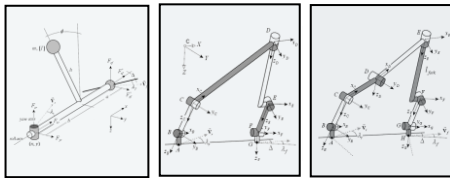
- Rigid bodies connected with ideal joints
- Nonlinear stiffness and damping curves
- Estimated tires parameters
- Model realized in **LMS Virtual.Lab Motion**
- In collaboration with **Piaggio**

17 bodies & 18 joints

➤ 13 DOF

Increasing complexity

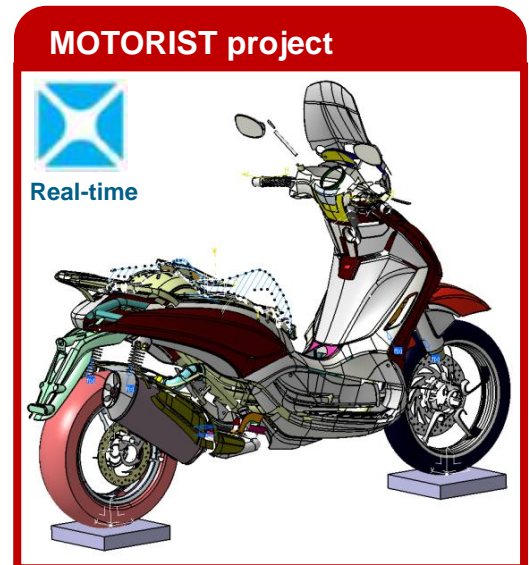
Previous project



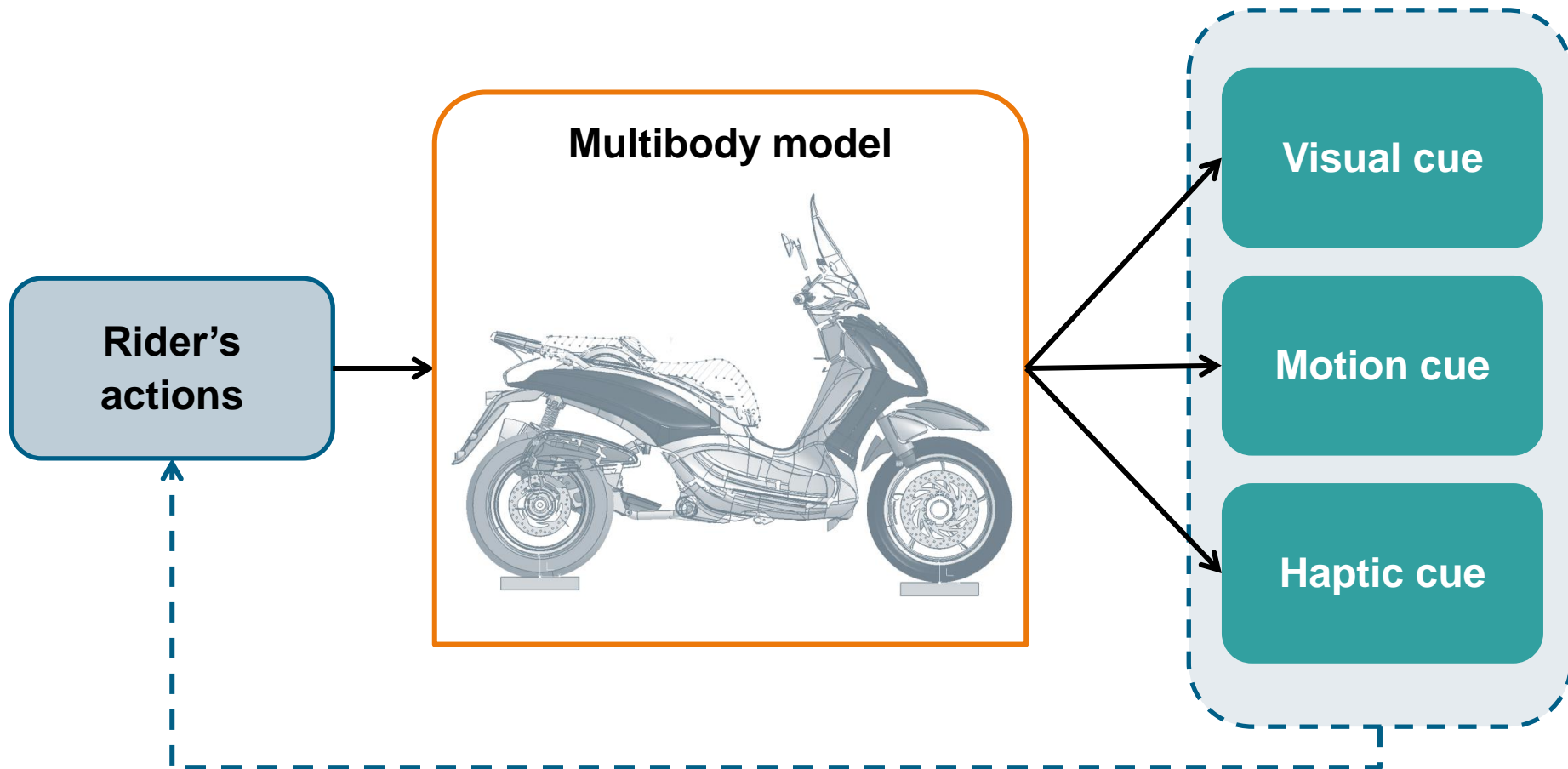
4DOF

9DOF

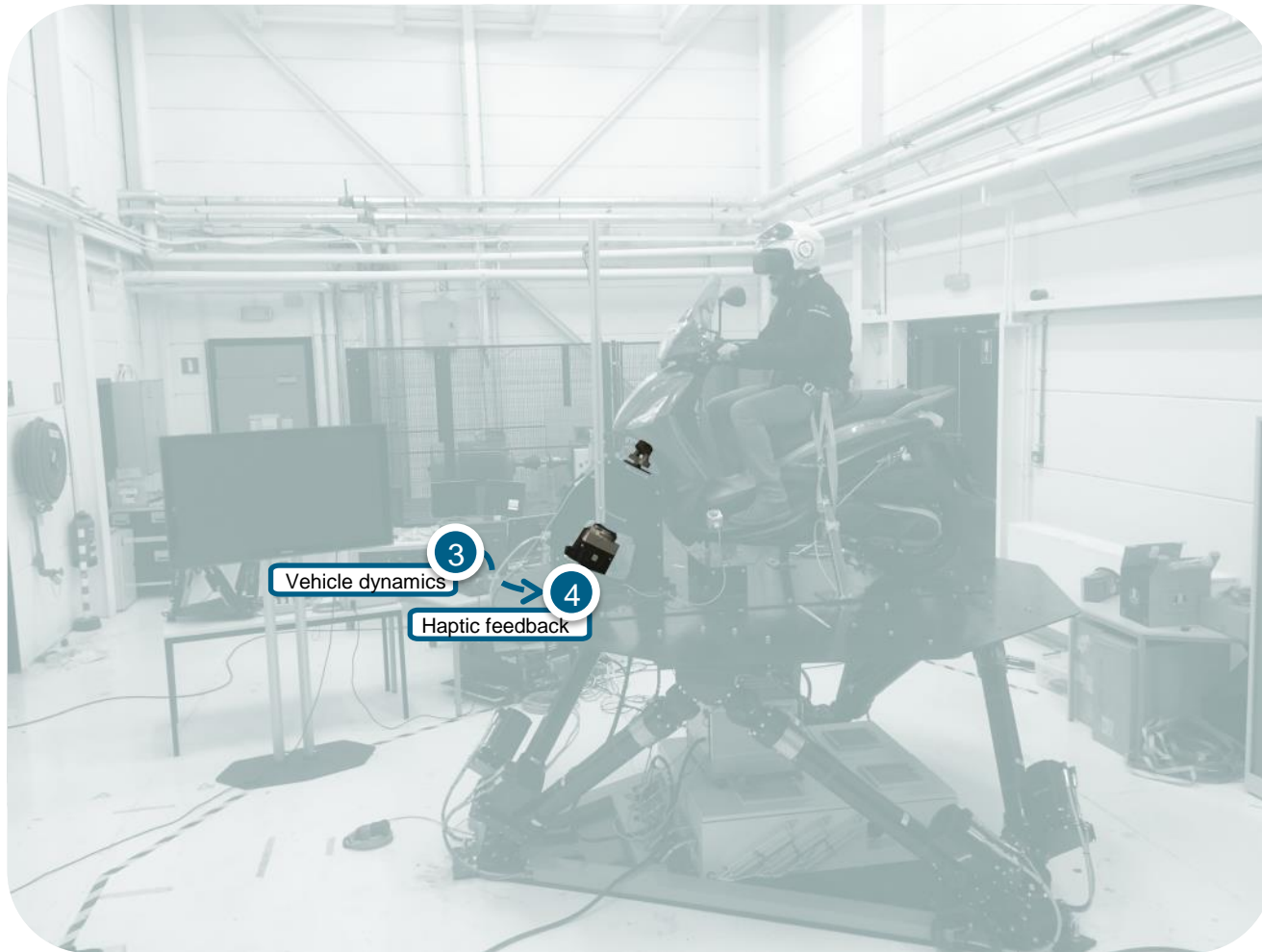
11DOF



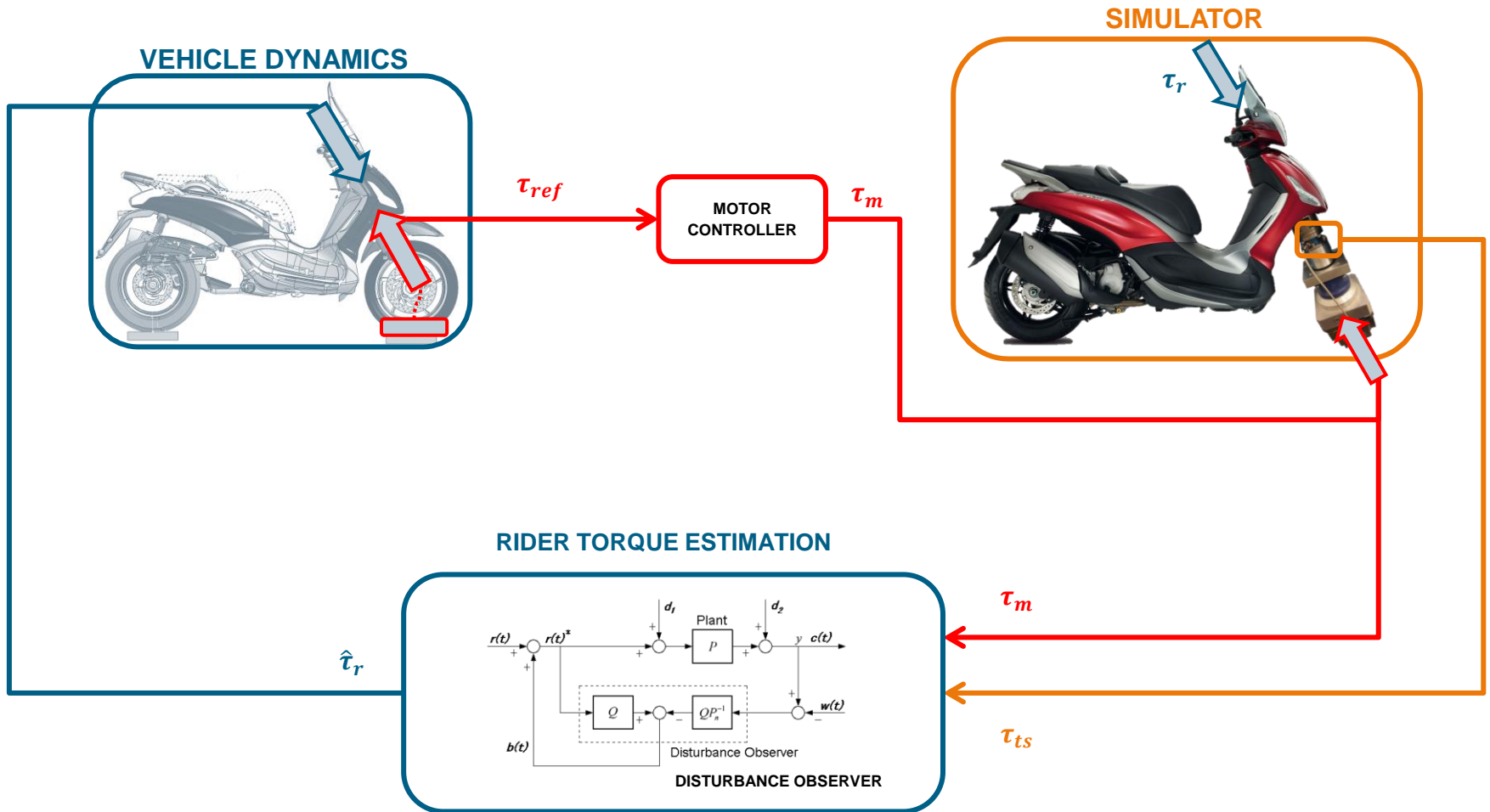
Multibody Model Simulation



MOTORIST simulator: overview



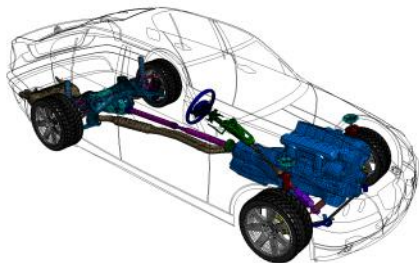
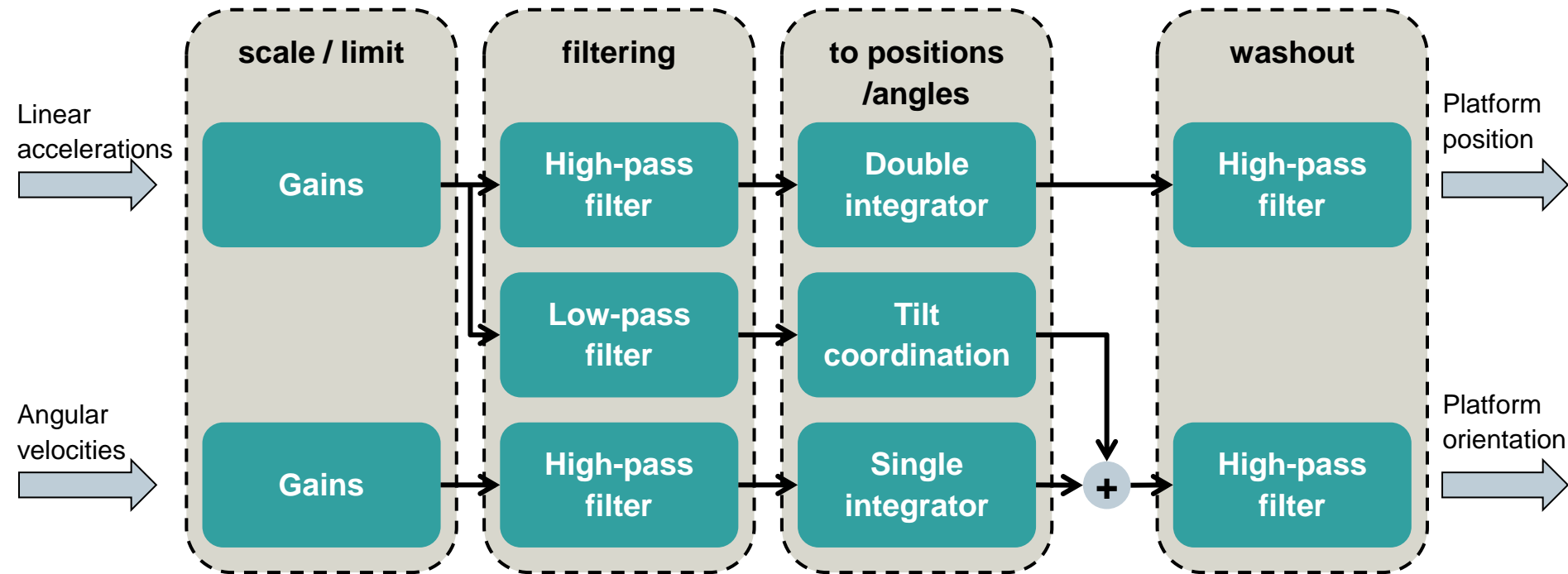
Haptic Feedback



MOTORIST simulator: overview



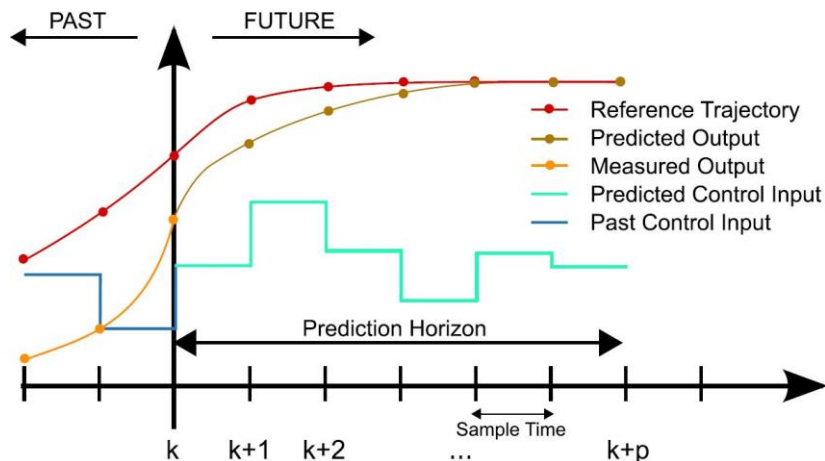
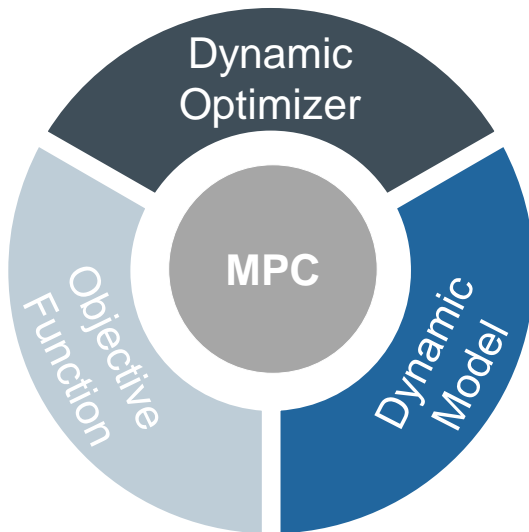
Classical cueing algorithm



- + Easy to tune
- + Parameters with physical meaning
- + Simple implementation
- Independent from driving scenario
- No advantages of full motion envelope



Conceptual MPC algorithm



MPC Controller needs to know:

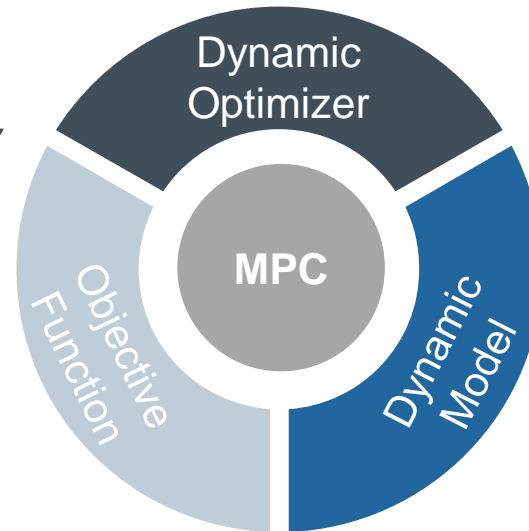
1. Which system it is working on
→ **Dynamic Model**
2. What goal it has to achieve
→ **Objective Function**
3. How to calculate the controls
→ **Dynamic Optimizer**

Possibility to consider the constraints in the optimization problem

MPC cueing



ACADO toolkit



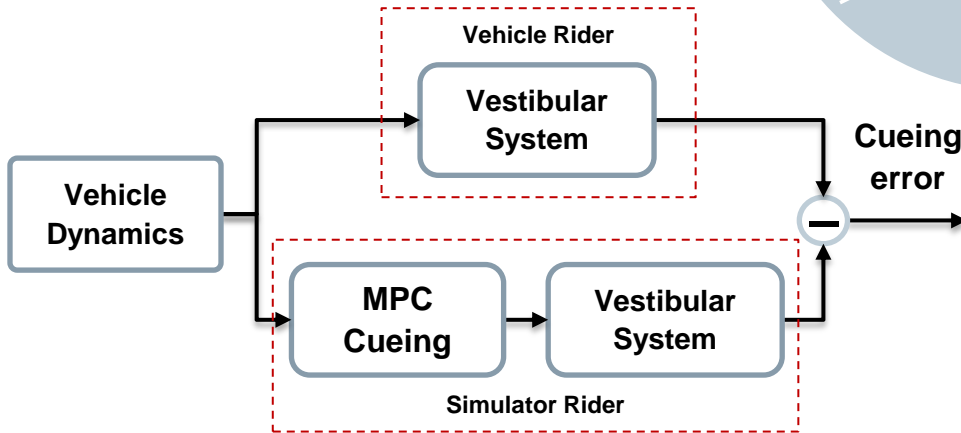
Minimize Cueing error

$$\Phi = \int_0^T L(t, x, u, p) dt + L_F(T, x(T), p(T))$$

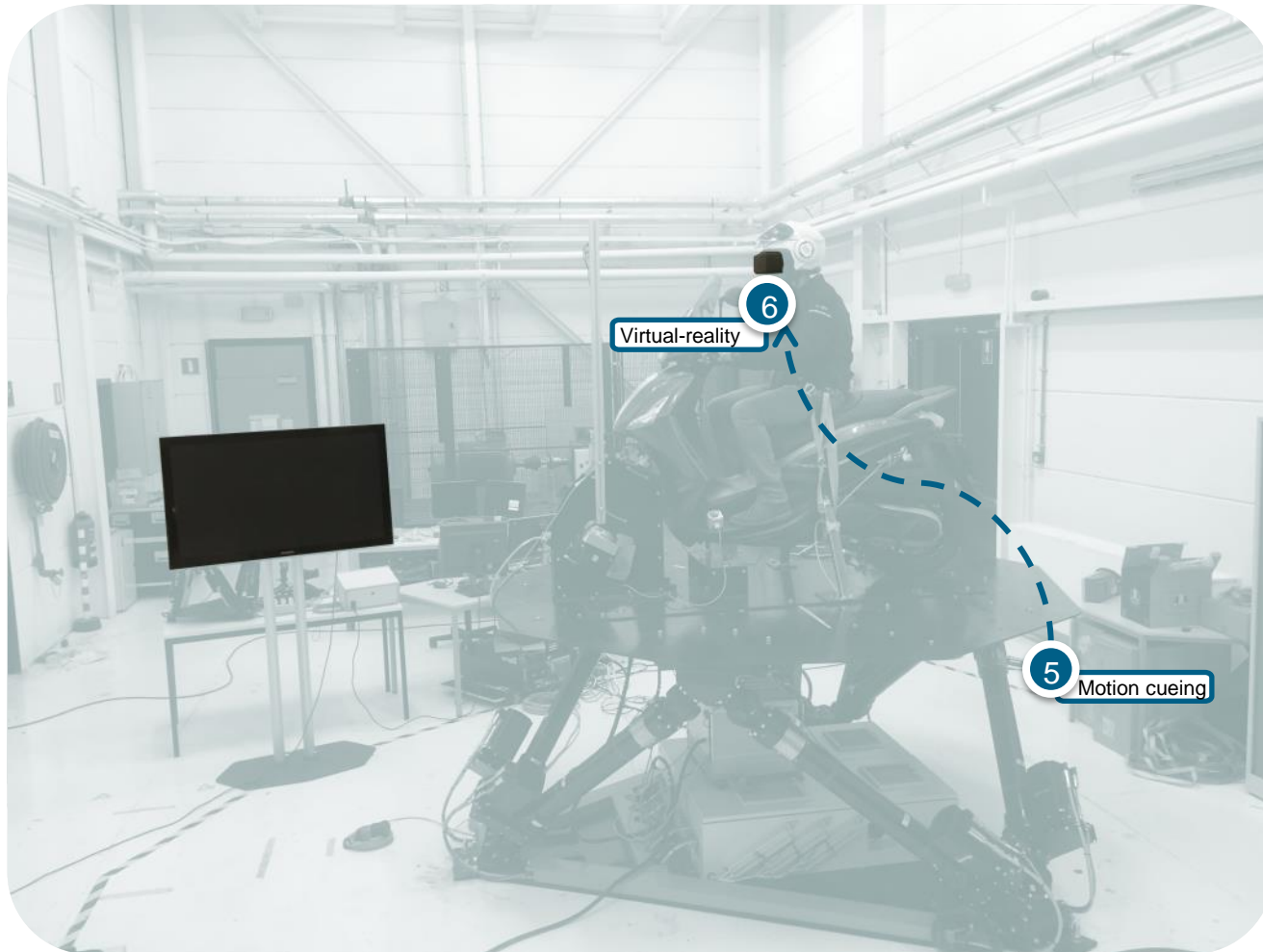
Vestibular System

$$\dot{x}_{vest} = A_{vest}x_{vest} + B_{vest}u$$

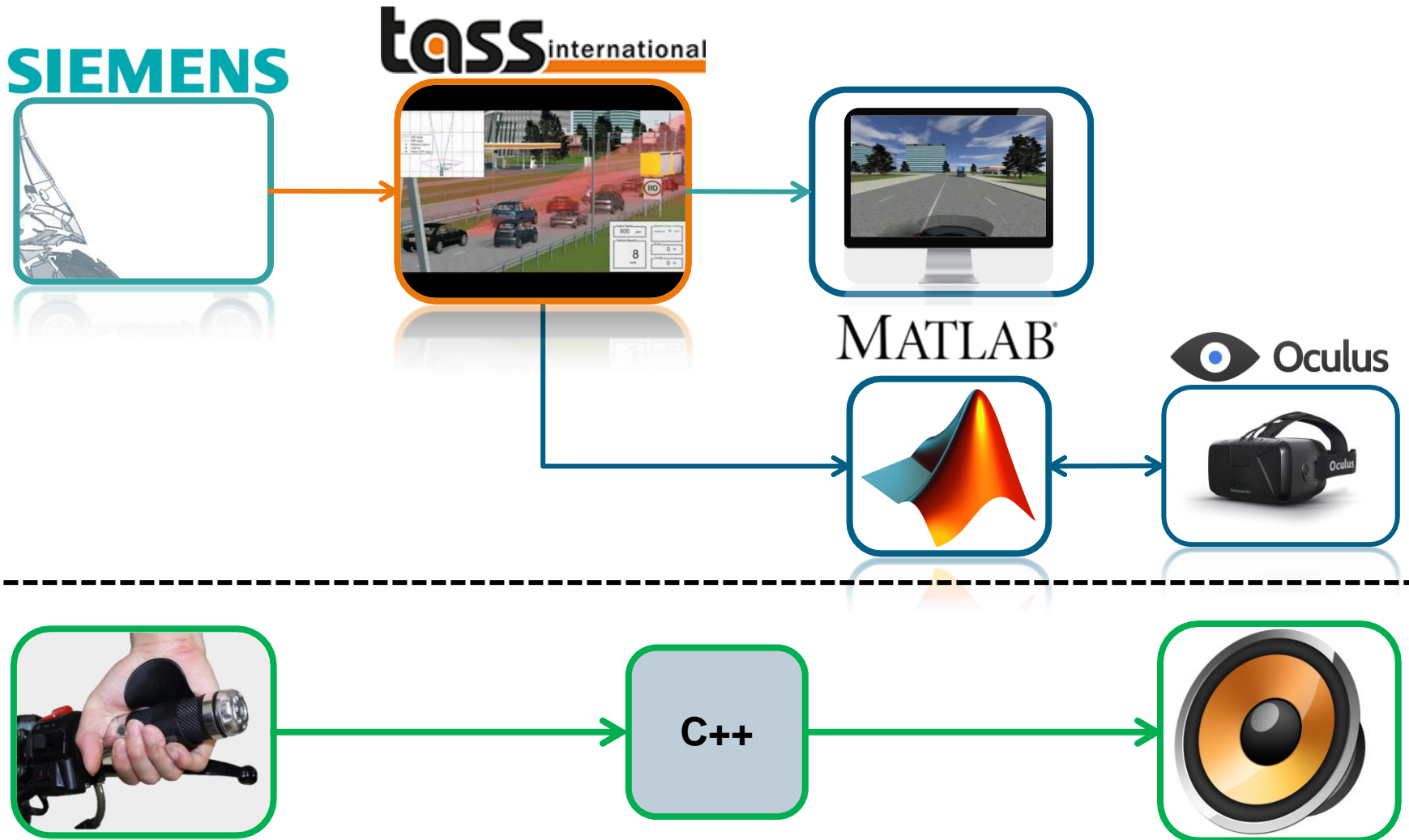
$$Y_{vest} = C_{vest}x_{vest} + D_{vest}u$$



MOTORIST simulator: overview



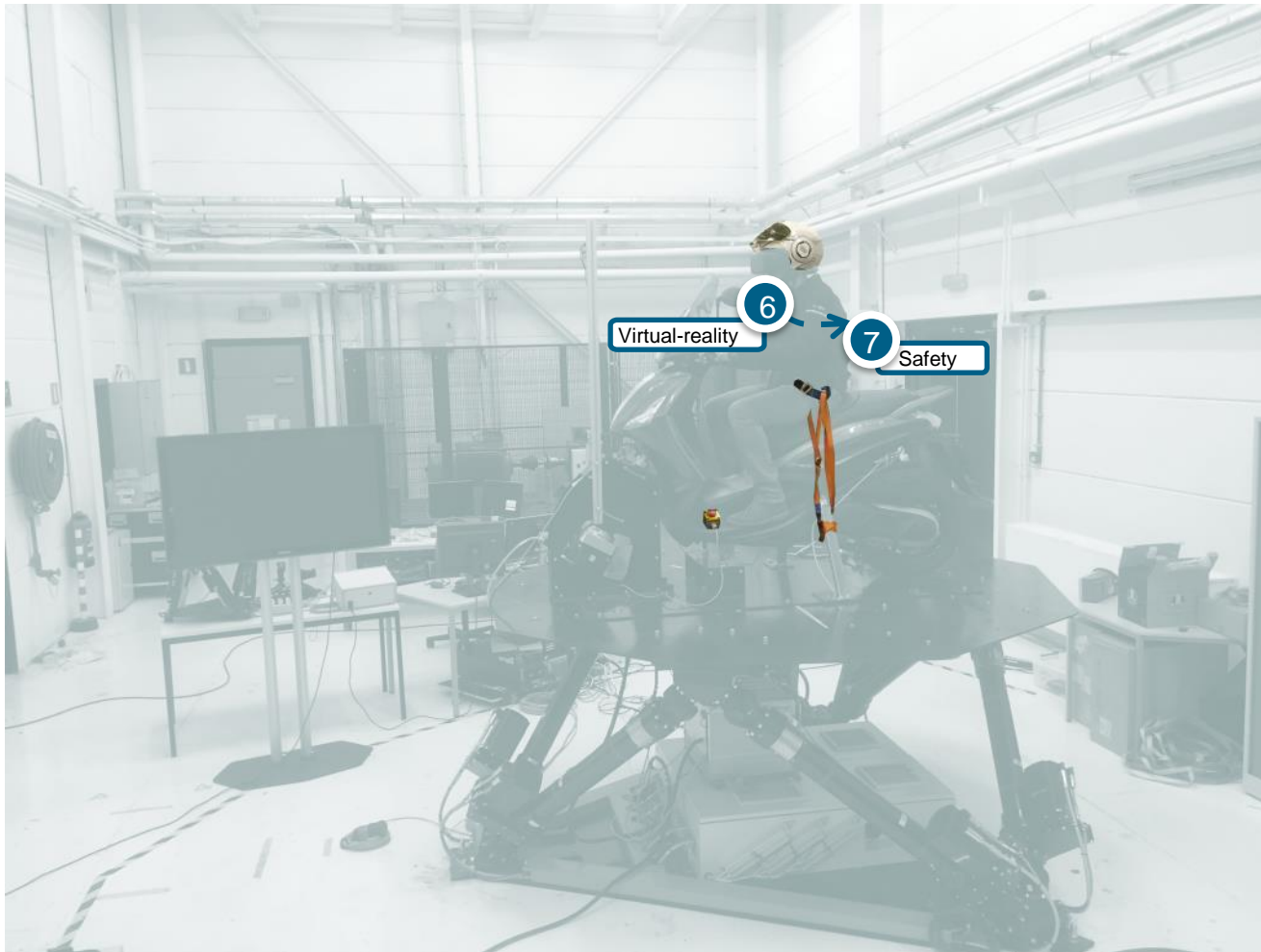
Visual/audio cues



Virtual Scenario

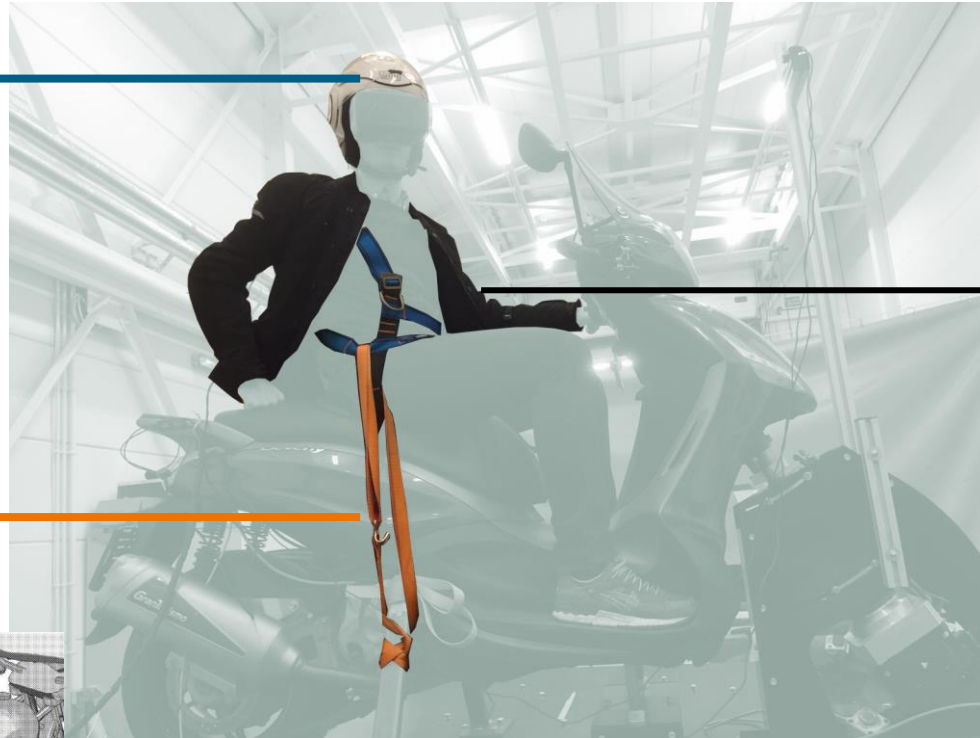


MOTORIST simulator: overview



Safety

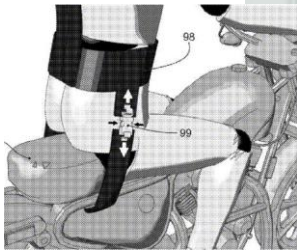
HELMET



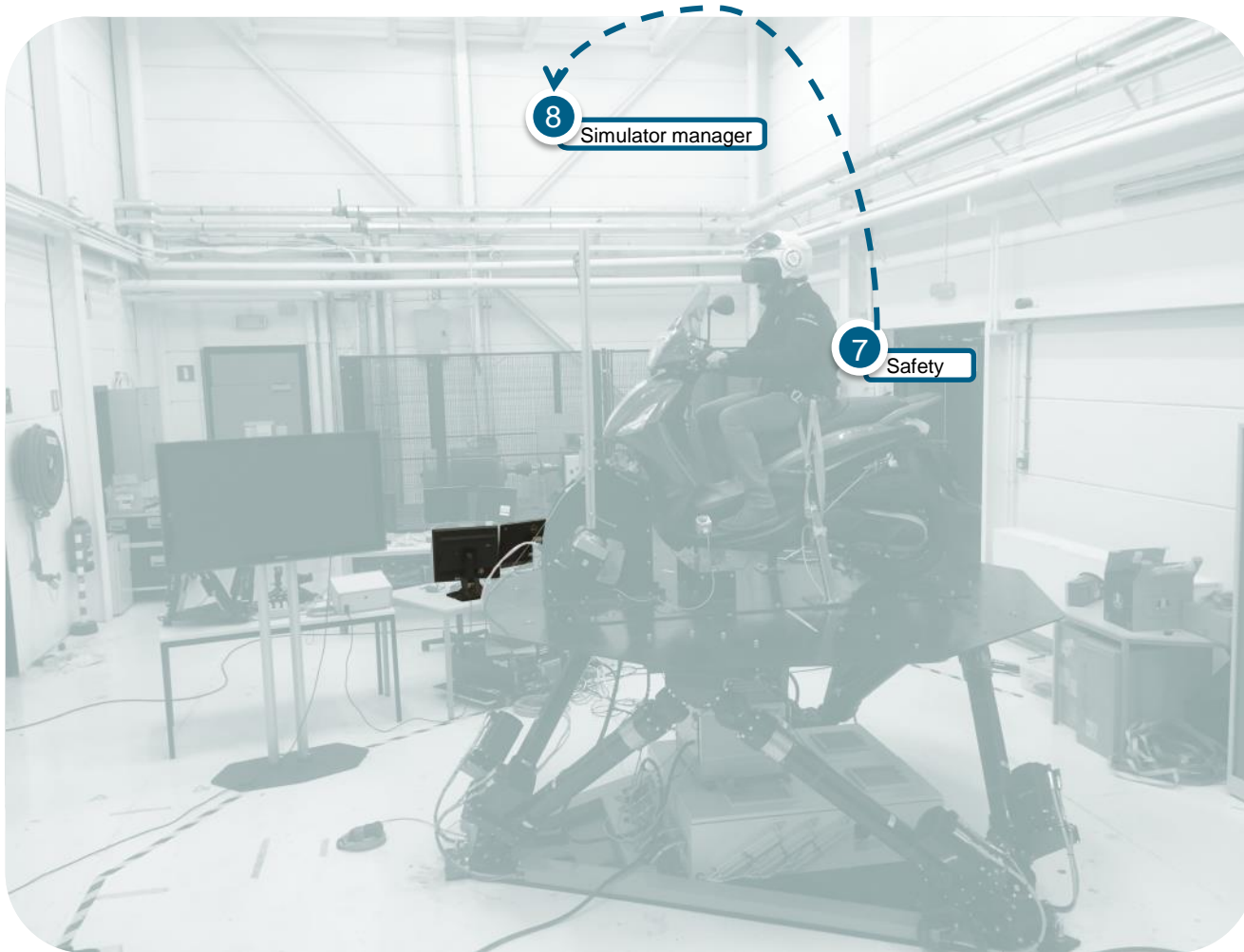
PROTECTIVE JACKET



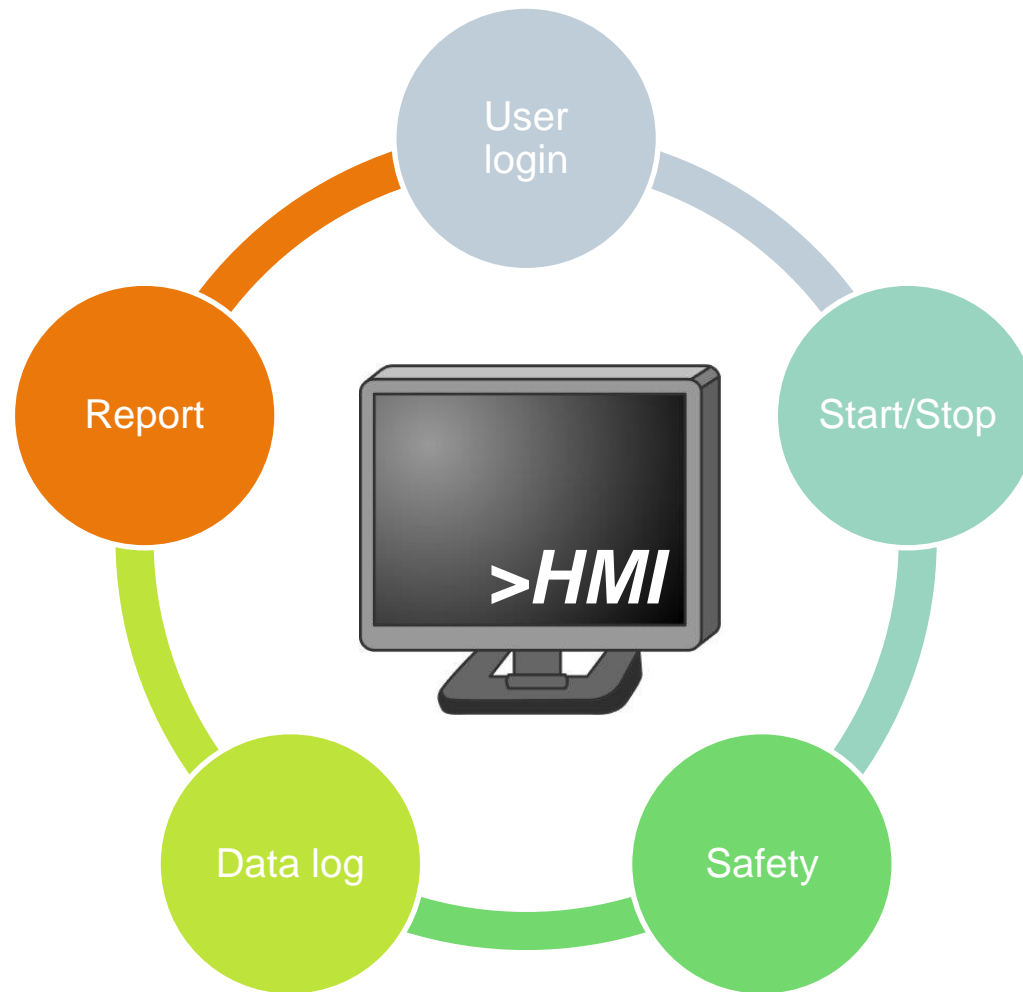
HARNESS



MOTORIST simulator: overview



Simulator manager



Data Logging Interface

→ Loading data file from remote machine

→ Rider personal data

→ Relevant data for training purposes

→ Generate report

Automatic reporting



MOTORIST Rider Report 23 November 2015

Name: *Francesco*

Age: 26

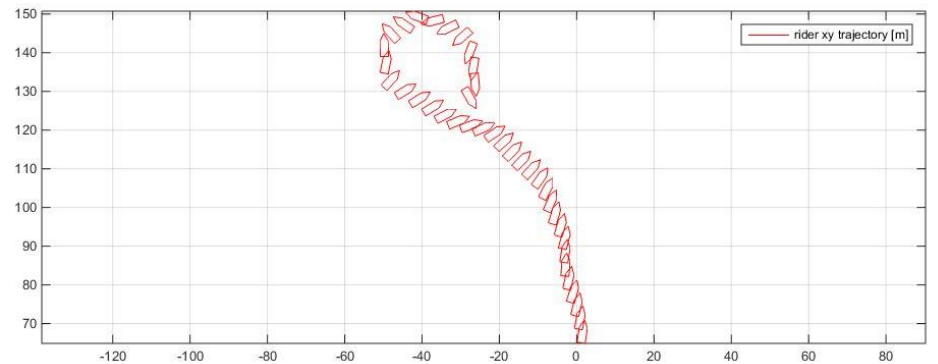
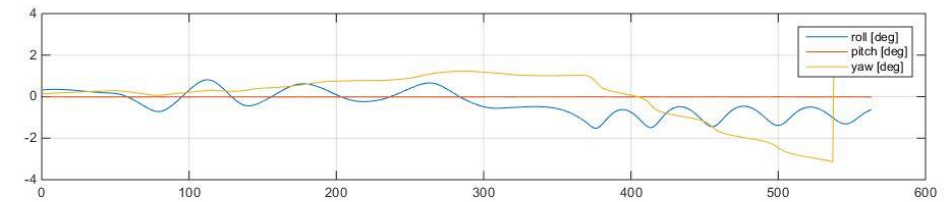
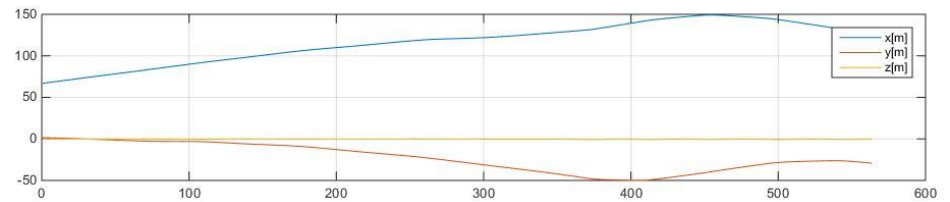
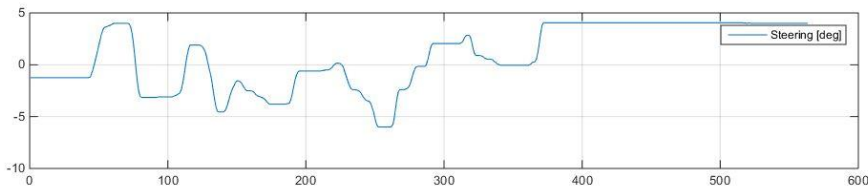
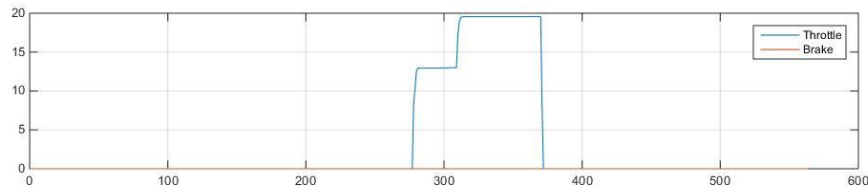
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Experience: 2

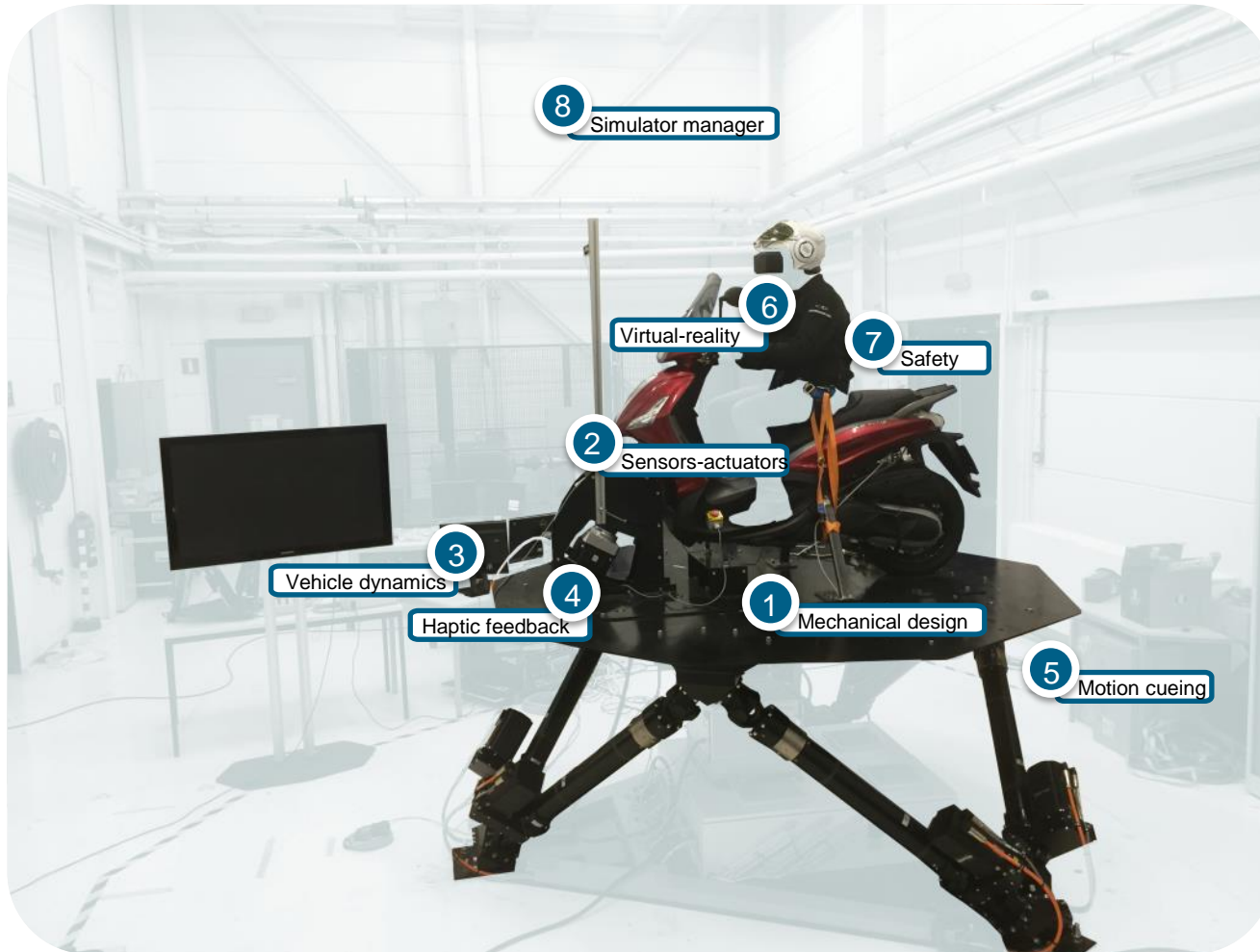
Surname: *Celiberti*

Nationality: *Italian*

Weight: 64



Thank you for the attention!





Thank you!

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