

## Scaling Methods

<b>Area:</b>	Scaled models for motor vehicles
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<b>Duration:</b>	2006 – 2009

The generation of collision-free trajectories is based on the method of the potential fields, where obstacles are modelled by repulsive spring forces. The trajectory is planned through discrete points created by the evasion model, which illustrate the internal force balance as a result of the acting potential fields. For the validation of the trajectory planning algorithms a 1:5 scaled model is built, which is characterised by the inclusion of a driver by means of a force feedback steering wheel.

