Abstract

Wheel slip control is a significant research topics in the field of car stability. Model predictive control is one of the most advanced controller which has received great attention and application in industries. In this paper independent model generalize predictive control (IMGPC) is introduced for anti-lock braking system. This controller is implemented on a linear model of anti-lock braking system, and through the numerical simulation, it is demonstrated that it can control the system in presence of sever noise and disturbances. The simulation results show that the proposed controller has better performance in comparison with other conventional linear controllers.


- J. A. Rossiter and G. Valencia-Palomo; Feed forward design in MPC; ECC, 2009.


Index Terms
Computer Science
Information Science
Keywords

Anti-lock braking system  generalized predictive control  ABS linearized model  robustness