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Moped and moped-rider kinematics — Vocabulary

AMENDMENT 1

*Cinématique relative au cyclomoteur et à son conducteur —
Vocabulaire*

AMENDEMENT 1

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Foreword

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AMENDMENT 1

Page 2, 3.2.1

Replace 3.2.1 with the following:

3.2.1

steering velocity

$\dot{\delta}$

angular velocity of the sprung part of the steering assembly about the z'_f -axis

Page 6, 5.2.7

Replace 5.2.7 with the following:

5.2.7

braking force

negative **tyre longitudinal force** (5.2.3) caused by the application of braking torque in the x_t -direction

Page 6, 5.2.8

Replace 5.2.8 with the following:

5.2.8

conicity force

tyre lateral force (5.2.2) which does not change sign [with respect to the **horizontal tyre axis system** (6.2.2)] with a change in direction of rotation when the **tyre slip angle** (5.1.5) and the **camber angle** (5.1.4) are zero

Page 6, 5.2.9

Replace 5.2.9 with the following:

5.2.9

plysteer force

tyre lateral force (5.2.2) which changes sign [with respect to the **horizontal tyre axis system** (6.2.2)] with a change in direction of rotation when the **tyre slip angle** (5.1.5) and the **camber angle** (5.1.4) are zero

Page 12, 6.7.6

Replace 6.7.6 with the following:

6.7.6

resultant roll angles

angles formed by the planes through either the x_{go} or x_{gg} or x_{ge} -axis and the moped-rider combination's centre of gravity and the z -axis; these are called respectively conventional ($\phi_{go,res}$), geometrical ($\phi_{gg,res}$) and effective ($\phi_{ge,res}$) resultant roll angle

Page 13, 6.7.9.7

Replace 6.7.9.7 with the following:

6.7.9.7

roll velocity

bank velocity

$\dot{\phi}$

angular velocity about the x' -axis

Page 13, 6.7.9.7.1

Replace 6.7.9.7.1 with the following:

6.7.9.7.1

conventional roll velocity

$\dot{\phi}_{go}$

angular velocity about the x_{go} -axis

Page 13, 6.7.9.7.2

Replace 6.7.9.7.2 with the following:

6.7.9.7.2

geometrical roll velocity

$\dot{\phi}_{gg}$

angular velocity about the x_{gg} -axis

Page 14, 6.7.9.7.3

Replace 6.7.9.7.3 with the following:

6.7.9.7.3

effective roll velocity

$\dot{\phi}_{ge}$

angular velocity about the x_{ge} -axis