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(54) Anti-lock control system in which road friction is calculated

(57) An anti-lock control system comprises wheel speed (VWL, VWR) detecting means (1L, 1R), wheel acceleration/deceleration detecting means (2L, 2R), means (3) for calculating a vehicle pseudo-speed (VRH) on the basis of a wheel speed (VWL, VWR) means (5) for storing a wheel speed (VWL, VWR) or vehicle pseudo-speed (VRH) at a sampling time at which the wheel acceleration/deceleration has become equal to or less than a preset (ao) set at a value at or near zero, after passing a peak in the course of increasing of the wheel speed (VWL, VWR), means (6) for calculating a speed difference (ΔV) between wheel speeds (VWL, VWR) or vehicle pseudo-speeds (VRH) stored currently and at a last time in the storing means (5), means (7) for counting the time lapsed (ΔT) from the last sampling time to the current sampling time, means (8) for dividing the speed difference (ΔV) by the lapsed time (ΔT) to provide a value ($\Delta V / \Delta T$) corresponding to a friction coefficient ($-\text{GRD1}$) of a road surface.

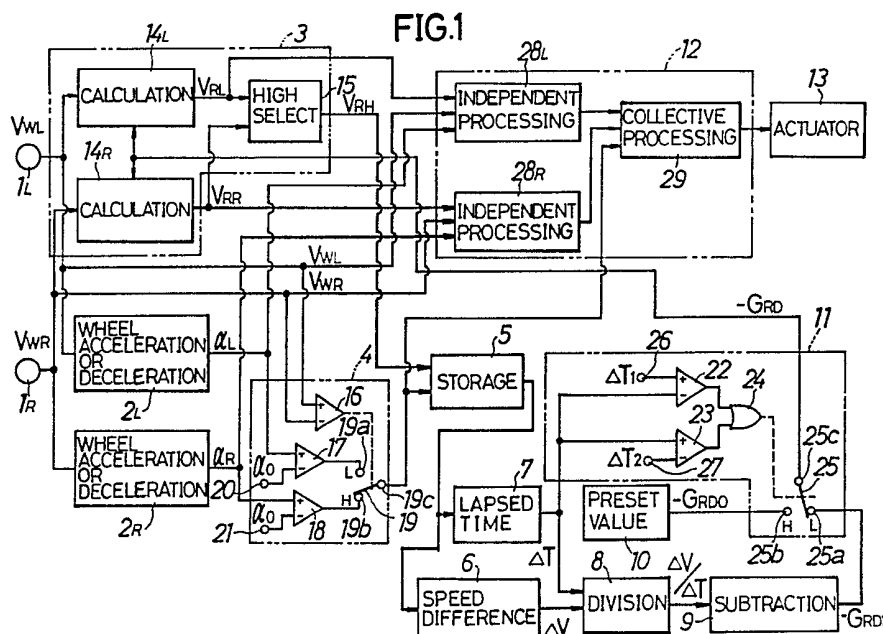


FIG. 1

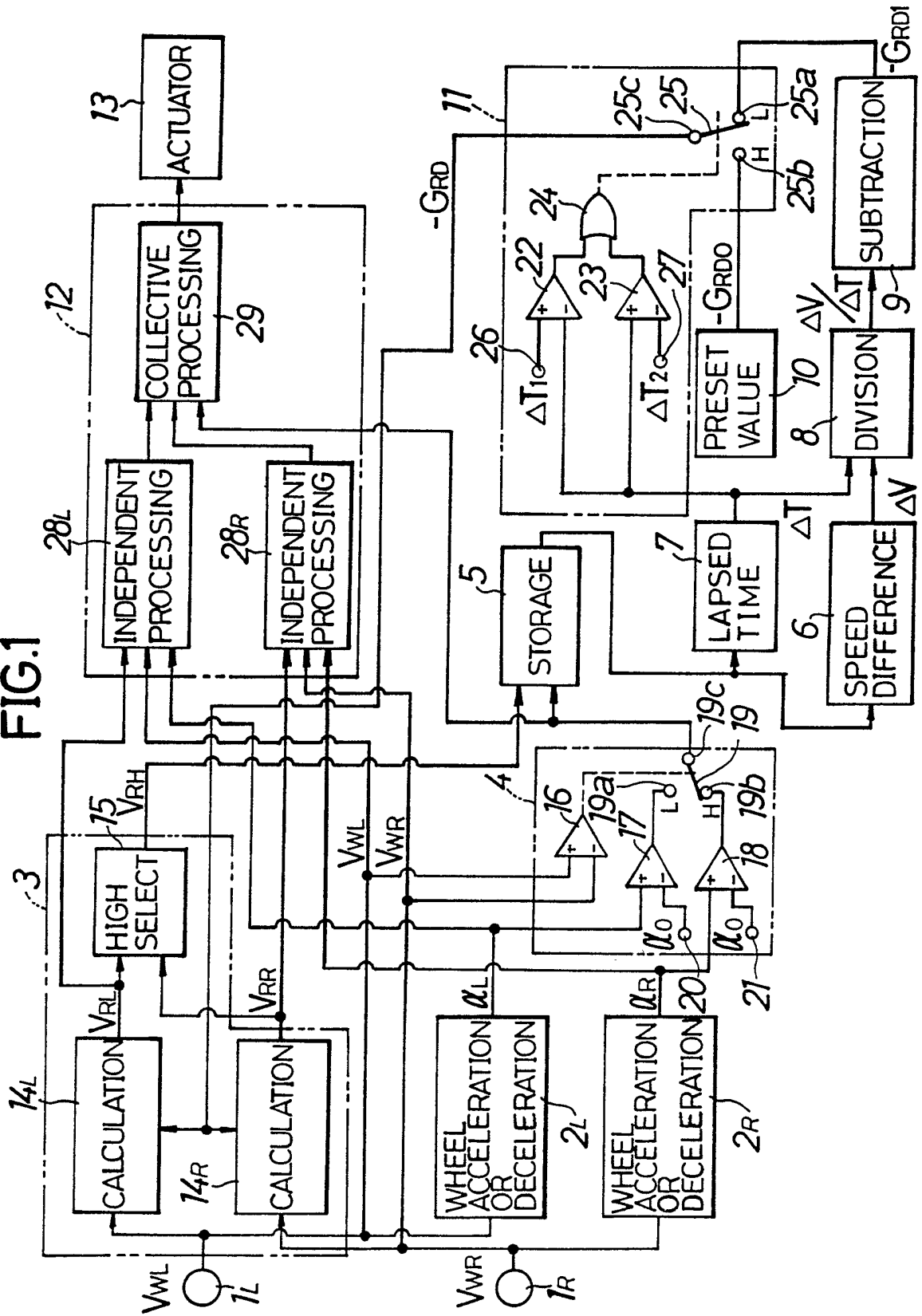
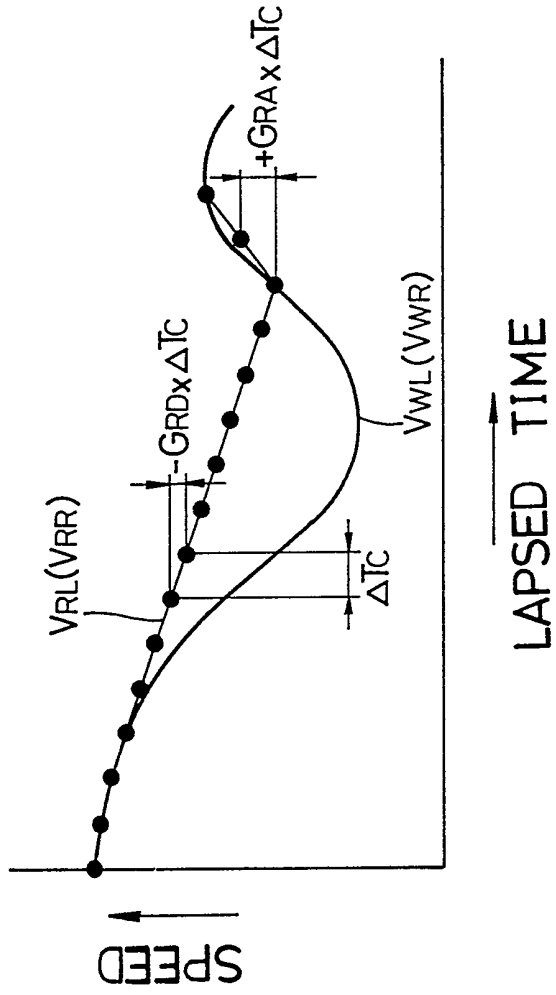


FIG. 2



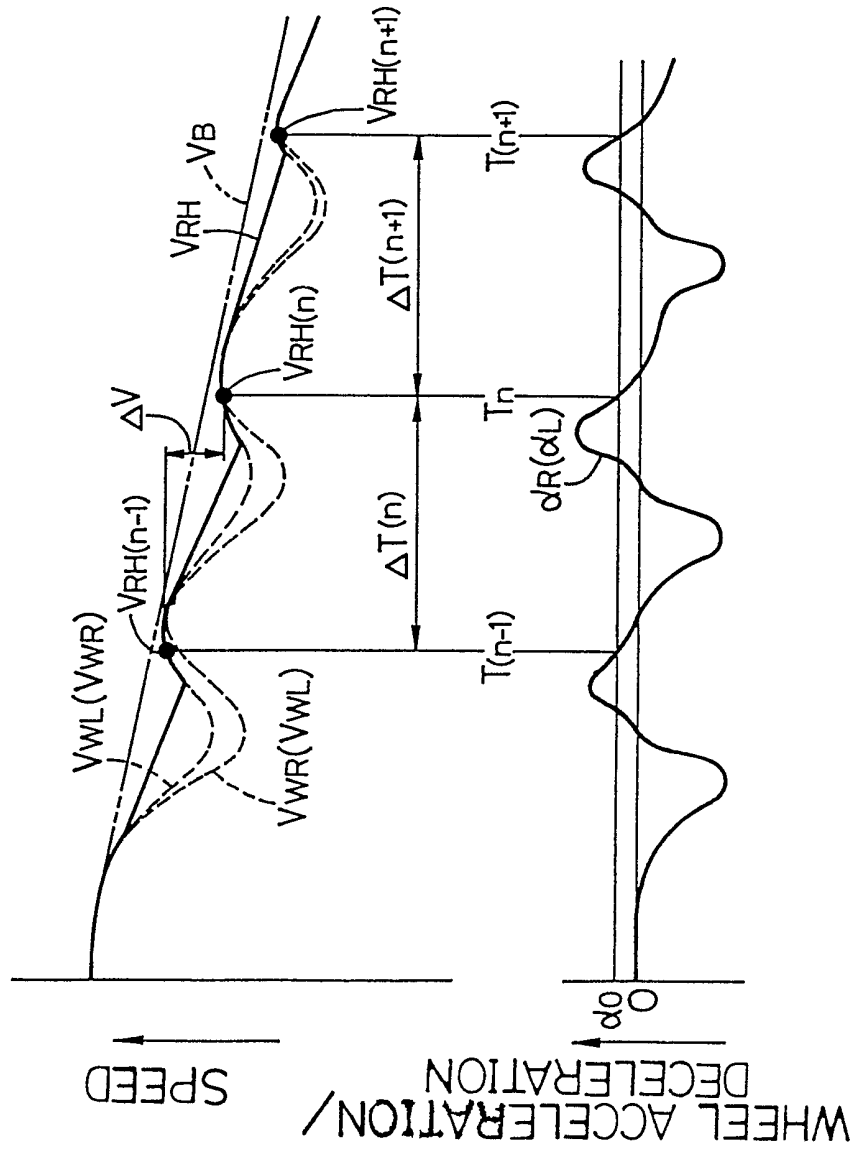


FIG. 3a

FIG. 3b

FIG.4

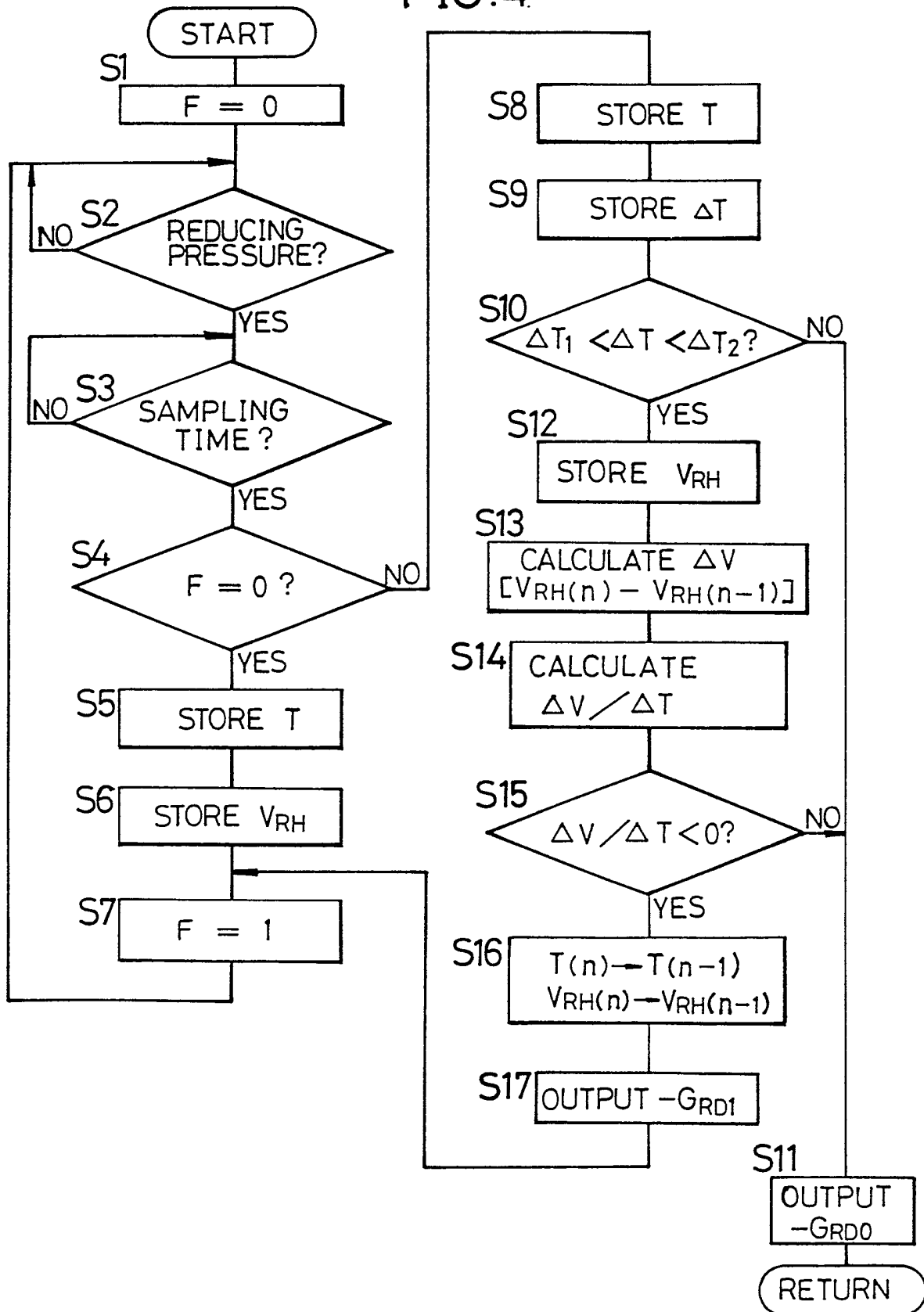
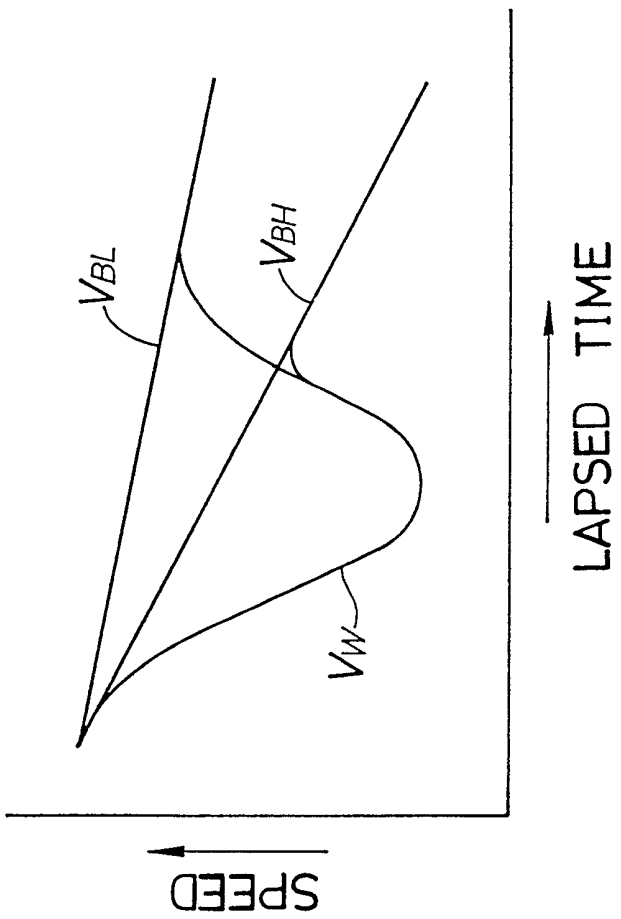


FIG.5



- 1 -
ANTI-LOCK CONTROL SYSTEM

The present invention relates to an anti-lock control system and, more particularly, to an anti-lock control system designed such that a value corresponding to a friction coefficient of a road surface on which a vehicle travels can be obtained, to enable an anti-lock control corresponding to the friction coefficient of the road surface.

An anti-lock control system is conventionally known from Japanese Patent Application Laid-Open No. 44039/80, which is designed such that the magnitude of friction coefficient of a road surface on which a vehicle travels is judged by the magnitude of a peak value of an acceleration in the course of restoring wheel speed to vehicle speed. An anti-lock control system is also conventionally known from Japanese Patent Application Laid-Open No. 155161/87, which is designed such that the magnitude of friction coefficient of a road surface on which a vehicle travels is judged by the magnitude of a restoring time between two speed points in the course of restoring of the wheel speed to a vehicle speed.

However, in the anti-lock control system disclosed in Japanese Patent Application Laid-Open No. 44039/80, the magnitude of friction coefficient is judged by measuring an acceleration at a pin point, and in the anti-lock control system disclosed in Japanese Patent Application Laid-Open No. 155161/87, a span between the measuring times is short. Therefore, in both such prior art anti-lock control systems,

the judgement of the magnitude of friction coefficient is governed by an instantaneous behaviour of the wheel. For this reason, it is difficult to judge the magnitude of friction coefficient, when the variations in wheel speed V_w with respect to the vehicle speed V_{BL} during travelling of the vehicle on a road surface of a low friction coefficient and the vehicle speed V_{BH} during travelling of the vehicle on a road surface of a high friction coefficient are substantially equal (see Fig. 5).

Accordingly, it is an object of the present invention to provide an anti-lock control system wherein a value, corresponding to a friction coefficient, can be obtained with a good accuracy without any influence by an instantaneous behaviour of the wheel.

To achieve the above object, according to a first aspect and feature of the present invention, there is provided an anti-lock control system comprising wheel speed detecting means; wheel acceleration/deceleration detecting means; vehicle pseudo-speed calculating means for calculating a vehicle pseudo-speed on the basis of a wheel speed detected by the wheel speed detecting means; storing means for storing a wheel speed or vehicle pseudo-speed at a sampling time at which the wheel acceleration or deceleration has become equal to or less than a preset acceleration set at a value near "0" (zero), including "0" (zero), after passing a peak in the course of increasing of the wheel speed; speed difference calculating means for calculating a speed difference between a wheel speed, or vehicle pseudo-speed, stored currently and the last time in

the storing means; lapsed-time counting means for counting the time lapsed from the last sampling time to the current sampling time; and division means for dividing the speed difference by the lapsed time to provide a value corresponding to a friction coefficient of a road surface.

With the first feature of the present invention, the value corresponding to the friction coefficient of the road surface can be obtained without any influence by an instantaneous behaviour of a wheel, and contributes to an enhancement in accuracy of an anti-lock control.

In addition to the above first feature, a second feature of the present invention is that the anti-lock control further includes set value output means for outputting a previously set value corresponding to the friction coefficient, in place of an output from the division means, when the lapsed time is out of a predetermined set range.

With the second feature of the present invention, the occasion of an extreme variation in behaviour of the wheel can be eliminated, and an erroneous operation, in the case of the extreme variation in behaviour of the wheel, can be avoided.

In addition to the above first feature, a third feature of the present invention is that the time of start of restoring and increasing of braking pressure is set at the sampling time.

With the third feature of the present invention, a value corresponding to a friction coefficient can be obtained using data at the time when the wheel speed is highest.

Further, in addition to the above first feature, a fourth feature of the present invention is that the braking pressures of a plurality of wheels are collectively controlled, the

sampling time is a time when the wheel acceleration of one of the plurality of wheels, which is liable to become locked, has become equal to or less than the preset acceleration after passing the peak, and the highest wheel speed of all the wheels, or a vehicle pseudo-speed calculated on the basis of the highest wheel speed, is inputted to the storing means at the sampling time.

With the fourth feature of the present invention, the accuracy of control can be enhanced by determining a storing timing for one of a plurality of synchronous wheel speeds, whose behaviour is significant and, thus, the wheel speed which is closest to the vehicle speed can be stored.

The above and other objects, features and advantages of the invention will become apparent from a consideration of the following description of the preferred embodiments, given by way of example, when taken in conjunction with the accompanying drawings, wherein:

Fig. 1 is a block circuit diagram illustrating the entire arrangement;

Fig. 2 is a graph illustrating a relationship between the wheel speed and the vehicle pseudo-speed;

Figs. 3a and 3b are diagrams for explaining the sampling time, the lapsed-time and the speed difference;

Fig. 4 is a flow chart illustrating a procedure of processing by a computer; and

Fig. 5 is a graph for explaining the disadvantage associated with the prior art.

Fig. 1 is a block circuit diagram illustrating an arrangement of a preferred embodiment of an anti-lock control system according to the present invention. The anti-lock control system is for collectively controlling braking pressures for left and right rear wheels of a vehicle and comprises wheel speed detecting means 1_L and 1_R for independently detecting wheel speeds V_{WL} and V_{WR} of the left and right rear wheels, wheel acceleration/deceleration detecting means 2_L and 2_R for providing wheel acceleration/deceleration α_L and α_R of the left and right wheels, respectively, from the wheel speeds V_{WL} and V_{WR} , vehicle pseudo-speed calculating means 3 for providing a vehicle pseudo-speed V_{RH} on the basis of the wheel speeds V_{WL} and V_{WR} , sampling-time determination means 4 for determining a sampling time, and storing means 5 for storing the vehicle pseudo-speed V_{RH} at the sampling time determined by the sampling-time determination means 4. The anti-lock control system further includes speed-difference calculating means 6 for calculating a speed difference ΔV between a vehicle pseudo-speed $V_{RH(n-1)}$ stored the last time in the storing means 5 and a vehicle pseudo-speed $V_{RH(n)}$ stored currently in the storing means 5, lapsed-time counting means 7 for counting a lapsed time ΔT from the last

sampling time to the current sampling time, division means 8 for dividing the speed difference ΔV by the lapsed time ΔT to provide a value corresponding to a friction coefficient of road surface, i.e., a deceleration ($\Delta V/\Delta T$) during execution of an anti-lock control, a subtraction means 9 for subtracting an offset value (ΔG) from the deceleration ($\Delta V/\Delta T$) to provide a deceleration ($-G_{RD1}$), set-value output means 10 for producing a set deceleration ($-G_{RDO}$) as a preset value corresponding to the friction coefficient, switchover means 11 for selecting any one of outputs from the subtraction means 9 and the set-value output means 10, depending upon whether or not the lapsed time ΔT counted by the lapsed-time counting means 7 is within a predetermined set range, and a control circuit 12, providing a control signal to an actuator 13, which controls the braking pressure of both the rear wheels.

The wheels speeds V_{WL} and V_{WR} of the left and right rear wheels, detected by the wheel speed detecting means 1_L and 1_R , are independently supplied to the wheel acceleration/deceleration detecting means 2_L and 2_R which differentiate the wheel speeds V_{WL} and V_{WR} to provide wheel acceleration/decelerations α_L and α_R .

The vehicle pseudo-speed calculating means 3 is comprised of a left rear wheel calculating circuit 14_L , for calculating a vehicle pseudo-speed V_{RL} on the basis of the left rear wheel speed V_{WL} provided in the wheel speed detecting means 1_L , a right rear wheel calculating circuit 14_R for calculating a vehicle pseudo-speed V_{RR} on the basis of the right rear wheel speed V_{WR} provided in the wheel speed detecting means 1_R , and a high select circuit 15 for selecting a higher one of the

vehicle pseudo-speeds V_{RL} and V_{RR} , outputted from the calculating circuits 14_L and 14_R , to output the selected higher one of the vehicle pseudo-speeds as a vehicle pseudo-speed V_{RH} .

In the left rear wheel calculating circuit 14_L , depending upon whether or not an acceleration/deceleration $\{(V_{RL(n-1)} - V_{WL(n)})/\Delta T_c\}$, provided by dividing a value of the current wheel speed $V_{WL(n)}$ subtracted from the last vehicle pseudo-speed $V_{RL(n-1)}$ by a time ΔT_c of a calculating cycle, is within a range defined by a limit deceleration ($-G_{RD}$) and a limit acceleration ($+G_{RA}$), a vehicle pseudo-speed $V_{RL(n)}$ is calculated in the following manner:

In a range represented by an expression, $-G_{RD} < (V_{RL(n-1)} - V_{WL(n)})/\Delta T_c < +G_{RA}$,

$$V_{RL(n)} = V_{RL(n-1)} - \{V_{RL(n-1)} - V_{WL(n)}\} = V_{WL(n)};$$

in a range represented by an expression, $(V_{RL(n-1)} - V_{WL(n)})/\Delta T_c \leq -G_{RD}$,

$$V_{RL(n)} = V_{RL(n-1)} - G_{RD} \times \Delta T_c; \text{ or}$$

in a range represented by an expression, $+G_{RA} \leq (V_{RL(n-1)} - V_{WL(n)})/\Delta T_c$,

$$V_{RL(n)} = V_{RL(n-1)} + G_{RA} \times \Delta T_c.$$

This gives the vehicle pseudo-speed V_{RL} , varied as shown in Fig. 2, with respect to the wheel speed V_{WL} .

On the other hand, in the right rear wheel calculating circuit 14_R , a vehicle pseudo-speed $V_{RR(n)}$ is calculated in the same manner as in the left rear wheel calculating circuit 14_L :

In a range represented by an expression, $-G_{RD} < (V_{RR(n-1)} - V_{WR(n)})/\Delta T_c < +G_{RA}$,

$$V_{RR(n)} = V_{RR(n-1)} - \{V_{RR(n-1)} - V_{WR(n)}\} = V_{WR(n)};$$

in a range represented by an expression, $(V_{RR(n-1)} - V_{WR(n)})/\Delta T_c \leq -G_{RD}$,

$$\leq -G_{RD},$$

$$V_{RR(n)} = V_{RR(n-1)} - G_{RD} \times \Delta T_C; \text{ or}$$

in a range represented by an expression, $+G_{RA} \leq (V_{RR(n-1)} - V_{WR(n)})/\Delta T_C,$

$$V_{RR(n)} = V_{RR(n-1)} + G_{RA} \times \Delta T_C.$$

The limit acceleration ($+G_{RA}$) is previously determined in view of a maximum acceleration assumed during travelling of the vehicle and a variation in wheel speed during travelling of a vehicle on a bad or muddy road, as well as a gradient of increase in wheel speeds during an anti-lock control and the like. The limit deceleration ($-G_{RD}$) is supplied as a value varied in correspondence to the friction coefficient of a road surface on which the vehicle travels, from the switchover means 11 to both the rear wheel calculating circuits 14_L and 14_R.

The sampling-time determination circuit 4 comprises comparators 16, 17 and 18, and a switch 19, whose switching mode is changed over in response to an output from the comparator 16. The wheel speed V_{WL} obtained in the wheel speed detecting means 1_L is applied to a non-inverted input terminal of the comparator 16, and the wheel speed V_{WR} , obtained in the wheel speed detecting means 1_R, is applied to an inverted input terminal of the comparator 16. Thus, the comparator 16 produces a high level signal when the left rear wheel speed V_{WL} is larger than the right rear wheel speed V_{WR} , and produces a low level signal when the right rear wheel speed V_{WR} is larger than the left rear wheel speed V_{WL} . The wheel acceleration/deceleration α_L obtained in the wheel acceleration/deceleration detecting means 2_L, is applied to a non-inverted input terminal of the comparator 17, and a preset acceleration α_0 , set at a

value near zero (0), including zero (0), is supplied from a reference terminal 20 to an inverted input terminal of the comparator 17. Further, the wheel acceleration/deceleration α_R obtained in the wheel acceleration/deceleration detecting means 2_R is applied to a non-inverted input terminal of the comparator 18, and the preset acceleration α_0 is supplied from the reference terminal 21 to an inverted input terminal of the comparator 18. Thus, each of the comparators 17 and 18 produces a high level signal, when the wheel acceleration/deceleration α_L, α_R is larger than the preset acceleration α_0 , and produces a low level signal, when the wheel acceleration/deceleration α_L, α_R is equal to or smaller than the preset acceleration α_0 .

The switch 19 is adapted to switch over the electric connection and disconnection between a common contact 19c and a separate contact 19a connected to an output terminal of the comparator 17, as well as a separate contact 19b connected to an output terminal of the comparator 18, and so that the separate contact 19b is electrically connected to the common contact 19c, when the left rear wheel speed V_{WL} is larger than the right rear wheel speed V_{WR} and the comparator 16 produces the high level signal, and the separate contact 19a is electrically connected to the common contact 19c, when the right rear wheel speed V_{WR} is larger than the left rear wheel speed V_{WL} and the comparator 16 produces the low level signal. In other words, on the one hand, when the left rear wheel speed V_{WL} is larger than the right rear wheel speed V_{WR} , a result of comparison of the right rear wheel acceleration/deceleration α_R with the preset acceleration α_0 is outputted from the common

contact 19c, and on the other hand, when the right rear wheel speed V_{WR} is larger than the left rear wheel speed V_{WL} , a result of comparison of the left rear wheel acceleration/deceleration α_L with the preset acceleration α_0 is outputted from the common contact 19c.

An output from the common contact 19c of the switch 19 and an output from the high select circuit 15 in the vehicle pseudo-speed calculating means 3 are received into the storing means 5, which stores the vehicle pseudo-speed V_{RH} received thereinto from the high select circuit 15 at a sampling time which is set to be a time when the output from the common contact 19c changed from the high level to the low level.

The operation of the storing means 5 and the sampling-time determination means 4 will be described below with reference to Figs. 3a-3b. In a condition where the left rear wheel speed V_{WL} and the right rear wheel speed V_{WR} (for example, $V_{WL} > V_{WR}$) are varied, as shown by broken lines in Fig. 3a, with respect to an actual vehicle speed V_B , the vehicle pseudo-speed V_{RH} , received into the storing means 5 from the high select circuit 5 in the vehicle pseudo-speed calculating means 3, is based upon the left rear wheel speed V_{WL} . On the other hand, in a condition where the left rear wheel speed V_{WL} is larger than the right rear wheel speed V_{WR} , the separate contact 19b and, thus, the comparator 18 is in electrical connection to the common contact 19c of the switch 19 in the sampling-time determination means 4. In this case, when the wheel acceleration/deceleration α_R of the right rear wheel becomes equal to or lower than the preset acceleration α_0 , after it has passed a peak in the course of increasing of the wheel speeds

V_{WL} and V_{WR} , as shown in Fig. 3b, vehicle pseudo-speeds $V_{RH(n-1)}$, $V_{RH(n)}$ and $V_{RH(n+1)}$, at sampling times $T_{(n-1)}$, $T_{(n)}$ and $T_{(n+1)}$ when the signal received in the storing means 5 from the sampling-time determination means 4 has been lowered, are sequentially stored in the storing means 5.

In the speed difference calculating means 6, a speed difference $\Delta V (= V_{RH(n)} - V_{RH(n-1)})$ between a vehicle pseudo-speed $V_{RH(n)}$ stored this time, or currently, in the storing means 5 and a vehicle pseudo-speed $V_{RH(n-1)}$, stored the last time in the storing means 5, is calculated. In the lapsed-time counting means 7, a lapsed-time ΔT from the last sampling time $T_{(n-1)}$ to the current sampling time $T_{(n)}$ is counted.

In the division means 8, Fig. 1, the speed difference ΔV , obtained in the speed difference calculating means 6, is divided by the lapsed time ΔT , obtained in the lapsed-time counting means 7, thereby providing a deceleration $(\Delta V/\Delta T)$ as a value corresponding to a friction coefficient of road surface.

In the subtracting means 9, a given value ΔG_R is subtracted from the deceleration $(\Delta V/\Delta T)$, obtained in the division means 8, to provide a limit deceleration $(-G_{RD1})$. That is, the calculation according to the following equation is carried out in the subtracting means 9:

$$-G_{RD1} = \Delta V/\Delta T - \Delta G_R.$$

This limit deceleration $(-G_{RD1})$ is used in the left and right rear wheel calculating circuits 14_L and 14_R in the vehicle pseudo-speed calculating means 3, and the vehicle pseudo-speeds V_{RL} and V_{RR} are provided using the limit deceleration $(-G_{RD1})$ in consideration of the deceleration $(\Delta V/\Delta T)$ corresponding to a

friction coefficient of road surface, leading to an increased accuracy of estimation of the vehicle pseudo-speeds V_{RL} and V_{RR} .

A given deceleration ($-G_{RDO}$), previously set as a maximum deceleration assumed during travelling of the vehicle, is outputted from the set-value output means 10. By the switchover operation of the switchover means 11, depending upon whether the lapsed-time ΔT obtained in the lapsed-time counting means 7 is within the predetermined set range, either one of the deceleration ($-G_{RD1}$), obtained in the subtracting means 9, and the given deceleration ($-G_{RDO}$), outputted from the set-value output means 10, is selected as a limit deceleration ($-G_{RD}$) and inputted to the left and right rear wheel calculating circuits 14_L and 14_R , respectively.

The switchover means 11 includes comparators 22 and 23, and OR gate 24 and a switch 25. The lapsed-time ΔT , obtained in the lapsed-time counting means 7, is applied to an inverted input terminal of the comparator 22 and a non-inverted input terminal of the comparator 23. On the other hand, a given time ΔT_1 is supplied from a reference terminal 26 to a non-inverted input terminal of the comparator 22, and another given time ΔT_2 , set longer than the given time ΔT_1 , is supplied from a reference terminal 27 to an inverted input terminal of the comparator 23. Then, outputs from the comparators 22 and 23 are inputted to the OR gate 24 in parallel.

The given time ΔT_1 is set to judge whether or not the period ΔT of sampling time is short enough for it to be decided that the vehicle is travelling on a bad or muddy road. The given time ΔT_2 is set to judge whether or not such period ΔT is long enough for it to be decided that a brake pedal is being

depressed with a low force for braking during travelling of the vehicle on a road surface of a relatively high friction coefficient.

A low level signal is outputted from the OR gate 24, only when $\Delta T_1 \leq \Delta T \leq \Delta T_2$, i.e., only when the vehicle is not travelling on a bad or muddy road and the brake pedal is not being depressed with a low force for braking during travelling of the vehicle on a road surface of a high friction coefficient. A high level signal is outputted from the OR gate 24, either when $\Delta T < \Delta T_1$, i.e. when it has been decided that the vehicle is travelling on a bad or muddy road, or when $\Delta T_2 < \Delta T$, i.e. when it has been decided that the brake pedal is being depressed with a low depression force for braking during travelling of the vehicle on a road surface of a high friction coefficient.

The switch 25 is adapted to switch over the electrical connection and disconnection between a separate contact 25a, connected to an output terminal of the subtracting means 9, as well as a separate contact 25b, connected to an output terminal of the set-value output means 10, and a common contact 25c, connected to the left and right rear wheel calculating circuits 14_L and 14_R in the vehicle pseudo-speed calculating means 3. When the output from the OR gate 24 is of a low level, the separate contact 25a is electrically connected to the common contact 25c, and when the output from the OR gate 24 is of a high level, the separate contact 25b is electrically connected to the common contact 25c. In other words, when the vehicle is not travelling on a bad or muddy road and the brake pedal is being not depressed with a low force for braking during

travelling of the vehicle on a road surface of a high friction coefficient, the deceleration ($-G_{RD1}$) obtained in the subtracting means 9 is inputted as the limit deceleration ($-G_{RD}$) into the left and right rear wheel calculating circuits 14_L and 14_R . When it has been decided that the vehicle is travelling on the bad or muddy road, or when it has been decided that the brake pedal is being depressed with a low force for braking during travelling of the vehicle on a road surface of a high friction coefficient, the given deceleration ($-G_{RD0}$), outputted from the set-value output means 10, is inputted as the limit deceleration ($-G_{RD}$) into the left and right rear wheel calculating circuits 14_L and 14_R .

The control circuit 12 includes a left rear wheel independently calculating section 28_L , a right rear wheel independently-calculating section 28_R and a collective control section 29. The left rear wheel speed V_{WL} , obtained in the wheel speed detecting means 1_L , the vehicle pseudo-speed V_{RL} from the left rear wheel calculating circuit 14_L in the vehicle pseudo-speed calculating means 3 and the left rear wheel acceleration/deceleration α_L , obtained in the wheel acceleration/deceleration detecting means 2_L , are inputted to the left rear wheel independently-calculating section 28_L . And the right rear wheel speed V_{WR} , obtained in the wheel speed detecting means 1_R , the vehicle pseudo-speed V_{RR} from the right rear wheel calculating circuit 14_R in the vehicle pseudo-speed calculating means 3 and the right rear wheel acceleration/deceleration α_R , obtained in the wheel acceleration/deceleration detecting means 2_R , are inputted to the right rear wheel independently-calculating section 28_R .

In the left rear wheel independently-calculating section 28_L, it is judged whether or not the left rear wheel is about to enter a locked state during braking, on the basis of the left rear wheel speed V_{WL} , a target wheel speed resulting from multiplication of the vehicle pseudo-speed V_{RL} , corresponding to the left rear wheel by a given slip rate, and the left rear wheel acceleration/deceleration α_L . Further, a control signal, indicative of a command to reduce, maintain or increase the braking pressure, depending upon a result of judgement, is inputted to the collective control section 29 from the left rear wheel independently-calculating section 28_L.

In the right rear wheel independently-calculating section 28_R, it is judged whether or not the right rear wheel is about to enter a locked state during braking, on the basis of the right rear wheel speed V_{WR} , a target wheel speed resulting from multiplication of the vehicle pseudo-speed V_{RR} corresponding to the right rear wheel by a given slip rate, and the right rear wheel acceleration/deceleration α_R . Further, a control signal, indicative of a command to reduce, maintain or increase the braking pressure, depending upon a result of judgement, is received into the collective control section 29 from the right rear wheel independently-calculating section 28_R.

The collective control section 29 selects one of the control signals for one of the rear wheels which is liable to become locked, on the basis of control signals, received from the independently-calculating sections 28_L and 28_R, to control the operation of the actuator 13, thereby collectively controlling the braking pressures for both the rear wheels. Moreover, the common contact 19c of the switch 19, in the

sampling-time determination means 4, is connected to the collective control section 29, and the collective control section 29 performs a braking-pressure restoring and increasing control with its starting time synchronized with a sampling time determined by the sampling-time determination means 4.

The operation of this embodiment will be described below. In calculating vehicle pseudo-speeds V_{RL} and V_{RR} during an anti-lock control, an instant when a wheel acceleration/deceleration of a lower one of the wheel speeds of the rear wheels, in the course of increasing the wheel speeds, e.g. α_L , has become lower than the preset acceleration α_0 , after passing a peak, is determined as a sampling time, the vehicle pseudo-speed V_{RH} outputted from vehicle pseudo-speed calculating means 3 at such sampling time, i.e. a higher one of vehicle pseudo-speed values V_{RL} and V_{RR} , calculated on the basis of the wheel speeds V_{RL} and V_{RR} of the rear wheels, is stored in the storing means 5.

In this manner, the vehicle pseudo-speed V_{RH} is stored in the storing means 5 at every sampling time determined by the sampling-time determination means 4. Thus, a deceleration $\Delta V/\Delta T$, corresponding to a friction coefficient of road surface, can be provided by dividing a difference ΔV between the vehicle pseudo-speeds $V_{RH(n)}$ and $V_{RH(n-1)}$ stored in the storing means 5 at the current sampling time and the last sampling time by an interval between the sampling times, i.e. a counted time ΔT . A deceleration ($-G_{RD1}$), calculated by using such deceleration $\Delta V/\Delta T$, is determined as a limit deceleration ($-G_{RD}$), whereby vehicle pseudo-speed V_{RL} and V_{RR} , as well as a target wheel speed, can be determined in correspondence to the friction

coefficient of road surface, which enables a more accurate anti-lock control.

Moreover, when the above-described counted time ΔT is smaller than ΔT_1 ($\Delta T < \Delta T_1$), i.e., short enough for it to be decided that the vehicle is travelling on a bad or muddy road, as well as when $\Delta T_2 < \Delta T$, i.e. when such counted time ΔT is long enough for it to be decided that the brake pedal is being depressed with a low depression force for braking during travelling of the vehicle on a road surface of a high friction coefficient, the given deceleration ($-G_{RD0}$) is used as the limit deceleration ($-G_{RD}$). Therefore, the erroneous setting of the limit deceleration ($-G_{RD}$) is avoided, and a value $(\Delta V/\Delta T)$, corresponding to the friction coefficient of road surface, can be determined with a good accuracy without any influence by an instantaneous behaviour of the wheel, leading to an improved accuracy of the anti-lock control.

In addition, the control accuracy can be further increased, because the sampling time is determined by a lower one of the wheel speeds of the rear wheels operated synchronously, i.e. the wheel speed of one of the rear wheels whose behavior is significant, and the vehicle pseudo-speed V_{RH} , stored in the storing means 5, is a higher speed selected from the vehicle pseudo-speed values.

Further, a value corresponding to a friction coefficient of road surface can be obtained using data when the wheel speed is highest at the start of restoring increase of the braking pressure synchronized with the sampling time.

A series of the above-described processings may be carried out by a computer, and in this case, a processing procedure

thereof is as shown in Fig. 4.

At a first step S1, a flag F is set at "0", and at a second step S2, it is judged whether or not the braking pressure is being reduced. When the braking pressure is being reduced, the processing is advanced to a third step S3 at which it is judged whether or not a sampling time has been now reached.

When it has been decided at the third step S3 that it is now a sampling time, it is judged at a fourth step S4 whether or not the flag F is of "0". If $F=0$, then time T and vehicle pseudo-speed V_{RH} are stored at fifth and sixth steps S5 and S6, respectively. The flag F is set at "1" at a seventh step S7 and thereafter, the processing is returned to the second step S2.

When the sampling time has been reached, the flag F is at "1" and, hence, the processing is advanced from the fourth step S4 to an eighth step S8, where the new sampling time T is stored. The processing is advanced to a ninth step S9 past the eighth step S8 and at the ninth step S9, a lapsed time ΔT between the sampling times is calculated. Further, at the tenth step S10, it is judged whether or not the lapsed time ΔT satisfies a relation of $\Delta T_1 < \Delta T < \Delta T_2$. When such relation is not satisfied, the given deceleration ($-G_{RDO}$) is outputted at an eleventh step S11. But if the relation of $\Delta T_1 < \Delta T < \Delta T_2$ is satisfied at the tenth step S10, a vehicle pseudo-speed V_{RH} at the current sampling time is stored at a twelfth step S12, and a speed difference ΔV is calculated at a thirteenth step S13 and, thereafter, the calculation of $\Delta V/\Delta T$ is carried out at a fourteenth step S14.

At a fifteenth step S15, it is judged whether or not the

$\Delta V/\Delta T$ indicates a negative value, i.e., a deceleration. If the $\Delta V/\Delta T$ indicates a positive value, i.e., an acceleration, then the processing is advanced to the eleventh step S11. If the $\Delta V/\Delta T$ indicates a deceleration, then the processing is advanced to a sixteenth step S16.

At the sixteenth step S16, the current sampling time $T_{(n)}$ is restored as the last sampling time $T_{(n-1)}$, and the current vehicle pseudo-speed $V_{RH(n)}$ is restored as the last vehicle pseudo-speed $V_{RH(n-1)}$. At a seventeenth step S17, the deceleration ($-G_{RD1}$) is outputted, returning to the seventh step S7.

In the above-described embodiment, the limit deceleration ($-G_{RD}$) for the calculation of the vehicle pseudo-speed has been corrected from the deceleration $\Delta V/\Delta T$ obtained as a value corresponding to the friction coefficient, and the magnitude of friction coefficient may be determined from the $\Delta V/\Delta T$, and so a control may be carried out with a relatively large gradient of increase in braking pressure at the time of restoring and increasing of the braking pressure, when the magnitude of friction coefficient is high, and, on the other hand, with a relatively small gradient of increase in braking pressure, when the magnitude of friction coefficient is low.

In addition, the value corresponding to the friction coefficient has been obtained by dividing the speed difference between the vehicle pseudo-speeds by the lapsed time in the above-described embodiment, but the value corresponding to the friction coefficient may be obtained by dividing the speed difference between the wheel speeds by the lapsed time.

Claims

1. An anti-lock control system comprising:
 - wheel speed detecting means;
 - wheel acceleration/deceleration detecting means;
 - vehicle pseudo-speed calculating means for calculating a vehicle pseudo-speed on the basis of a wheel speed detected by the wheel speed detecting means;
 - storing means for storing a wheel speed or vehicle pseudo-speed at a sampling time at which the wheel acceleration/deceleration has become equal to or less than a preset acceleration set at a value near or equal to zero after passing a peak in the course of increasing of the wheel speed;
 - speed difference calculating means for calculating a speed difference between wheel speeds or vehicle pseudo-speeds stored currently and the last time in the storing means;
 - lapsed-time counting means for counting the time lapsed from the last sampling time to the current sampling time; and
 - division means for dividing said speed difference by the lapsed time to provide a value corresponding to a friction coefficient of a road surface.

2. An anti-lock control system according to claim 1, further including set value output means for outputting a previously set value corresponding to the friction coefficient in place of an output from the division means, when the lapsed time is out of a predetermined set range.

3. An anti-lock control system according to claim 1 or 2, wherein the time of start of restoring and increasing of braking pressure is set at the sampling time.

4. An anti-lock control system according to claim 1, 2 or 3, wherein the braking pressures of a plurality of wheels are collectively controlled, the sampling time is a time when the wheel acceleration of one of the plurality of wheels which is liable to become locked has become equal to or less than the preset acceleration after passing the peak, and the highest wheel speed of all the wheels or a vehicle pseudo-speed calculated on the basis of said highest wheel speed is inputted to said storing means at said sampling time.

5. An anti-lock control system according to claim 4, wherein the sampling time is a time when the acceleration of the wheel having the lowest wheel speed has become equal to or less than the preset acceleration after passing the peak.

6) An anti-lock control system according to any preceding claim, wherein the vehicle pseudo-speed is calculated on the basis of the road surface friction coefficient.

7. An anti-lock control system substantially as hereinbefore described with reference to Figs. 1 to 3.

8. An anti-lock control system substantially as hereinbefore described with reference to Fig. 4.

Patents Act 1977
 Examiner's report to the Comptroller under
 Section 17 (The Search Report)

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Relevant Technical fields

(i) UK Cl (Edition K) F2F

(ii) Int Cl (Edition 5) B60T

Search Examiner

T M JAMES

Databases (see over)

(i) UK Patent Office

(ii) ONLINE DATABASES: WPI

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31 JULY 1992

Documents considered relevant following a search in respect of claims

1-8

Category (see over)	Identity of document and relevant passages	Relevant to claim(s)
X	US 4704684 (KUBO) See Figure 30 and column 29 lines 22-37	at least Claim 1



Category	Identity of document and relevant passages	Relevance to claim(s)

Categories of documents

- X:** Document indicating lack of novelty or of inventive step.
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