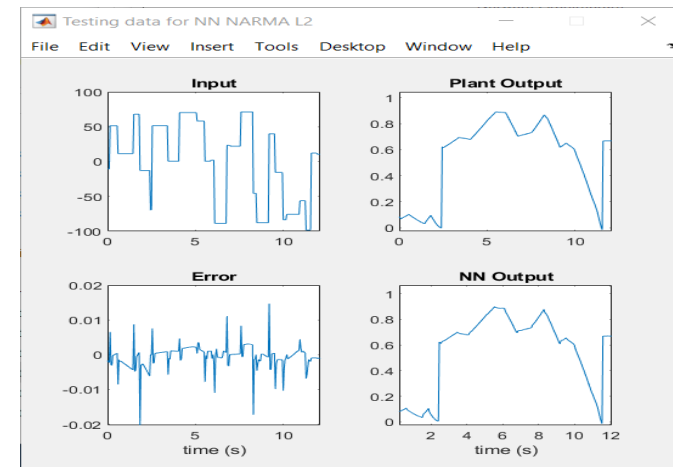


Longitudinal Wheel Slip Regulation using NARMA-L2 Neural Controller

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- Implemented a nonlinear autoregressive-moving average model (NARMA-L2) neural network controller to maximize the traction of tires during braking scenarios
- Proposed controller and system dynamics was done in Simulink
- Experienced peak worst error of around 2%; best performance was reached after 89 epochs; can reach around 99.5% of the reference trajectory or desired slip ratio



Testing data for NARMA-L2 neural controller