

7. REFERENCES

- Canudas de Wit, C., Olsson, H., Astrom, K.J. and Lischinsky, P., 1995, "A New Model for Control Systems with Friction", IEEE Transactions on Automatic Control, Vol. 40, n. 3, pp.419-425.
- Chee Shin Yeo, Buyya, R., Pourreza, H., Eskicioglu, R., Graham, P., and Sommers, F., 2006, "Cluster Computing: High-Performance, High-Availability, and High-Throughput Processing on a Network of Computers", Handbook of Nature-Inspired and Innovative Computing: Integrating Classical Models with Emerging Technologies, chapter 16, Pages: 1-24.
- Iagnemma, K. and Dubowsky, S., 2004, "Mobile Robots in Rough Terrain: Estimation, Motion Planning, and Control with Application to Planetary Rovers". Series: Springer Tracts in Advanced Robotics, August 17 2004, Vol. 12, 1st ed., Springer.
- Iagnemma, K. and Dubowsky, S., 2004, "Traction Control of Wheeled Robotic Vehicles in Rough Terrain with Application to Planetary Rovers". The International Journal of Robotics Research, October 2004, vol. 23, no. 10-11 1029-1040 .
- Morrot, R., 2010, "Simulação Tridimensional em Tempo-Real de Veículos Robóticos em Terrenos Acidentados", M.Sc. Thesis, Mech. Eng. Dept., Pontifical Catholic University of Rio de Janeiro, Brazil (In Portuguese).
- Pacejka, H.B., 2006, "Tire and Vehicle Dynamics", SAE – Society of Automotive Engineers, Inc., Second Edition, pp. 156-215.
- Peters, S.C. and Iagnemma, K., 2009, "Stability measurement of high-speed vehicles.", Vehicle System Dynamics, Vol. 47 Issue 6, pp.701-720.
- Santos, A.V., 2007, "Controle de Capotagem e Deslizamento de Sistemas Robóticos Móveis em Terrenos Acidentados", M.Sc. Thesis, Mech. Eng. Dept., Pontifical Catholic University of Rio de Janeiro, Brazil (In Portuguese).
- Silva, A.F.B., 2007, "Modelagem de Sistemas Robóticos Móveis para Controle de Tração em Terrenos Acidentados", M.Sc. Thesis, Mech. Eng. Dept., Pontifical Catholic University of Rio de Janeiro, Brazil (In Portuguese).
- Silva, A.F.B., Santos, A.V., Meggiolaro, M.A. and Neto, M.S., 2010, "A Rough Terrain Traction Control Technique For All-Wheel-Drive Mobile Robots", Journal of the Brazilian Society of Mechanical Sciences and Engineering, 2010, ABCM.
- Sobczuk, S., Mario, R., Perondi, E.A. and Cunha, M.A.B., 2009, "A Continuous Approximation Of The LuGre Friction Model", 20th International Congress Of Mechanical Engineering – COBEM 2009, November 15-20, Gramado, RS, Brazil.

8. RESPONSIBILITY NOTICE

The authors are the only responsible for the printed material included in this paper.