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ISO 11838

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AMENDMENT 1
2011-05-01

Motorcycle and motorcycle-rider kinematics — Vocabulary

AMENDMENT 1

Cinématique relative au motocycle et à son conducteur — Vocabulaire

AMENDEMENT 1

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Foreword

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Attention is drawn to the possibility that some of the elements of this document may be the subject of patent rights. ISO shall not be held responsible for identifying any or all such patent rights.

Amendment 1 to ISO 11838:1997 was prepared by Technical Committee ISO/TC 22, *Road vehicles*, Subcommittee SC 22, *Motorcycles*.

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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 7, 5.2.7

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Replace 5.2.7 with the following:

5.2.7

braking force

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

Page 7, 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 7, 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 13, 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 motorcycle-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 14, 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 14, 6.7.9.7.1

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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 <https://standards.iteh.ai/catalog/standards/sist/1028688e-04d4-43eb-8676-1e59b0c1d114/iso-11838-1997-amd-1-2011>

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Page 14, 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

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