contents

Used	d Symb	ols	<u>xi</u>
Prefa	ace		<u>xxi</u>
Fore	word I		<u>xxiii</u>
Fore	word I		XXV
Abo	ut the I	Editor	<u>xxvii</u>
CH.	APTER	1	
Int	rodu	ction	1
		dger Frerichs, Prof. DrIng. Marcus Geimer, and Huhtala	
CH.	APTER	2	
Ch	assis		9
Mark		dger Frerichs, Prof. DrIng. Marcus Geimer, la Motte, Fabrizio Panizzolo, and opes	
2.1	Cons Freri	truction of Mobile Working Machines (By Ludger chs)	<u>9</u>
	2.1.1	Requirements and Influences	<u>10</u>
		Basic Structures and Frame Concepts	<u>13</u>
	2.1.3	Design Principles	<u>20</u>
2.2		s (By Fabrizio Panizzolo)	<u>26</u>
		Axle Architecture	<u>27</u>
2.3		Fundamental Axle Components	<u>32</u>
		Fire Interaction (By Marcus Geimer)	<u>37</u>
2.4		Steering Systems (By Markus de la Motte and Thomas Pippes)	
	2.4.1	Design and Functions of Hydraulically Assisted Steering Systems	<u>45</u>
	2.4.2	Design and Functions of Semi-Active and Active Steering Systems	<u>51</u>
Refe	rences		<u>55</u>

©2020 SAE International

СНА	PTER	3	
Pov	ver -	Train	61
Edwir	n Heen	n, Prof. Danilo Engelmann, DrIng. Gerhard Geerling, nskerk, DrIng. Torsten Kohmäscher, Fabrizio Panizzolo, istian Pohlandt, and Prof. DrIng. Heinrich Steinhart	
3.1	Primary Energy Provision (By Danilo Engelmann and Christian Pohlandt)		
	3.1.1	Primary Energy Carriers	62 62
	•	Characteristics of Prime Movers	64
	3.1.3	Combustion Engines	66
	3.1.4	Electric Storage	72
3.2	Kohm	s of Power Conversion (By Swen Bosch, Torsten näscher, Fabrizio Panizzolo, and Heinrich	
	Stein	·	<u>75</u>
		Mechanic Energy Conversion Hydraulic Energy Conversion	<u>76</u> 94
		Electric Energy Conversion	104
3.3	Tracti	ion Drive (By Torsten Kohmäscher and Fabrizio	104
	Paniz	•	<u>113</u>
		Mechanical Gearboxes	<u>113</u>
		Hydrodynamic Transmission	<u>118</u>
		Hydrostatic Transmission	<u>129</u>
		Power-Split Transmission	<u>142</u>
3.4	Function Drives (By Gerhard Geerling and Edwin Heemskerk)		160
		Basic Pilot Actuation (PA) Principles	162
	3.4.2	Basic Pump (P) Control Principles	166
	3.4.3	Basic Valve Principles	<u>169</u>
	3.4.4	Well-Established Systems for Hydraulic Function	
	7 1 5	Drives	<u>177</u>
		Comparison between the Systems	202
Refer	ences		<u> 206</u>
CHA	PTER	4	_
			711
	ا ۱۱۱ ار f Hawl	·	<u>211</u>
<i>Detie</i>	ı mawl.	ILZEK	
4.1	Requ	irements and Trends	<u>211</u>
	4.1.1	Electronics and Hydraulics	<u>212</u>
	4.1.2	Safety	212

	4.1.3	Driver Assistance Systems	<u>212</u>
	4.1.4	Logging of Operational Data	<u>214</u>
	4.1.5	Networking	<u>215</u>
4.2	Cont	roller and Sensors	<u>215</u>
	4.2.1	Requirements	<u>215</u>
	4.2.2	PWM and Dither	<u>218</u>
4.3	Auto	mation Technologies	222
	4.3.1	Machines with a Central Controller	<u>222</u>
	4.3.2	Machines with Decentralized Control Technology/ Distributed Intelligence	<u>223</u>
4.4	Comi	munication and Networking	225
		Bus Systems in Mobile Working Machinery Telemetry and Remote Service	<u>225</u> 236
4.5	Func	tional Safety Aspects in Mobile Working Machines	<u>244</u>
	4.5.1	The Standards	<u>246</u>
	4.5.2	Safety Integrity	<u>248</u>
	4.5.3	Right Assessment and Consistent Implementation	<u>248</u>
Refe	rences		<u>254</u>
CHA	APTER	5	
Inn	ovat	rive Drive Concepts	<u>257</u>
		seem Daher, Prof. DrIng. Marcus Geimer, Ivantysyn	
5.1	Innov		
	1111101	ative Hybrid Drive Systems	<u> 260</u>
	5.1.1	vative Hybrid Drive Systems Introduction	260 261
	5.1.1 5.1.2	Introduction	
	5.1.1 5.1.2	Introduction Series-Parallel Hybrid Displacement Controlled Systems Coupled Displacement Controlled Actuation	<u>261</u>
	5.1.1 5.1.2	Introduction Series-Parallel Hybrid Displacement Controlled Systems	<u>261</u> <u>264</u>
5.2	5.1.1 5.1.2 5.1.3 5.1.4	Introduction Series-Parallel Hybrid Displacement Controlled Systems Coupled Displacement Controlled Actuation A Blended Hydraulic Hybrid System for On-Road Vehicles	261 264 267
5.2	5.1.1 5.1.2 5.1.3 5.1.4	Introduction Series-Parallel Hybrid Displacement Controlled Systems Coupled Displacement Controlled Actuation A Blended Hydraulic Hybrid System	261 264 267 272
5.2	5.1.1 5.1.2 5.1.3 5.1.4 Innov 5.2.1	Introduction Series-Parallel Hybrid Displacement Controlled Systems Coupled Displacement Controlled Actuation A Blended Hydraulic Hybrid System for On-Road Vehicles rative Displacement Controlled Linear Drive Systems	261 264 267 272 275
5.2	5.1.1 5.1.2 5.1.3 5.1.4 Innov 5.2.1 5.2.2	Introduction Series-Parallel Hybrid Displacement Controlled Systems Coupled Displacement Controlled Actuation A Blended Hydraulic Hybrid System for On-Road Vehicles vative Displacement Controlled Linear Drive Systems Introduction	261 264 267 272 275 275
5.2	5.1.1 5.1.2 5.1.3 5.1.4 Innov 5.2.1 5.2.2 5.2.3	Introduction Series-Parallel Hybrid Displacement Controlled Systems Coupled Displacement Controlled Actuation A Blended Hydraulic Hybrid System for On-Road Vehicles rative Displacement Controlled Linear Drive Systems Introduction Closed Circuit Linear Drive Example	261 264 267 272 275 275 282

5.3	Furth	er Innovative DC Machine Concepts	<u>294</u>
	5.3.1	Closed Circuit Flow Sharing Concept	<u>294</u>
	5.3.2	DC Steer-By-Wire Technology	<u> 295</u>
	5.3.3	Active Vibration Damping Using Swashplate Control	<u>299</u>
	5.3.4	Pump Vibration Damping Using Swashplate Control	<u>302</u>
	5.3.5	Secondary Control and Hydraulic Transformers	<u>305</u>
5.4	Furth	er Innovative Systems	<u>309</u>
	5.4.1	Digital Hydraulics	<u>309</u>
	5.4.2	Independent Metering	<u>313</u>
	5.4.3	Sustainable Energy Sources	<u>314</u>
Refe	rences		<u>316</u>
	APTER		
Sel	ecte	d Machine Examples	<u>323</u>
	-	ner Bavendiek, Dr. Martin Kremmer, and	
DrII	ng. Her	bert Pfab	
6.1	Tract	or (By Martin Kremmer)	<u>323</u>
	6.1.1	Introduction	<u>323</u>
	6.1.2	Concept and Configurations	<u>333</u>
	6.1.3	Interfaces for Applications	<u>340</u>
	6.1.4	Tractor Applications	<u>351</u>
6.2	Whee	el Loader (By Herbert Pfab)	<u>356</u>
	6.2.1	Application	<u>358</u>
	6.2.2	Machine Concepts	<u>360</u>
	6.2.3	Process Connection	<u> 365</u>
	6.2.4	Traction Drive	<u>372</u>
	6.2.5	Drivers Cab	<u>380</u>
6.3	Forkl	ift Truck (By Rainer Bavendiek)	<u>383</u>
	6.3.1	Classification and Standards	<u>384</u>
	6.3.2	Requirements and Main Functions	<u>386</u>
	6.3.3	Frame and Counterbalance	<u>393</u>
	6.3.4	Powertrain	<u>395</u>
	6.3.5	Hydraulics	<u>399</u>
	6.3.6	Operator Working Place	<u>402</u>
	6.3.7	Electric Controls and Software	<u>407</u>
	6.3.8	Mast and Attachments	<u>410</u>
	6.3.9	Trends and Future Developments	<u>411</u>
Refe	rences		413

CHAPTER 7	
Summary	<u>421</u>
Prof. DrIng. Marcus Geimer	
About the Authors	<u>425</u>
Mobile Working Machines	<u>431</u>
Index	<u>433</u>