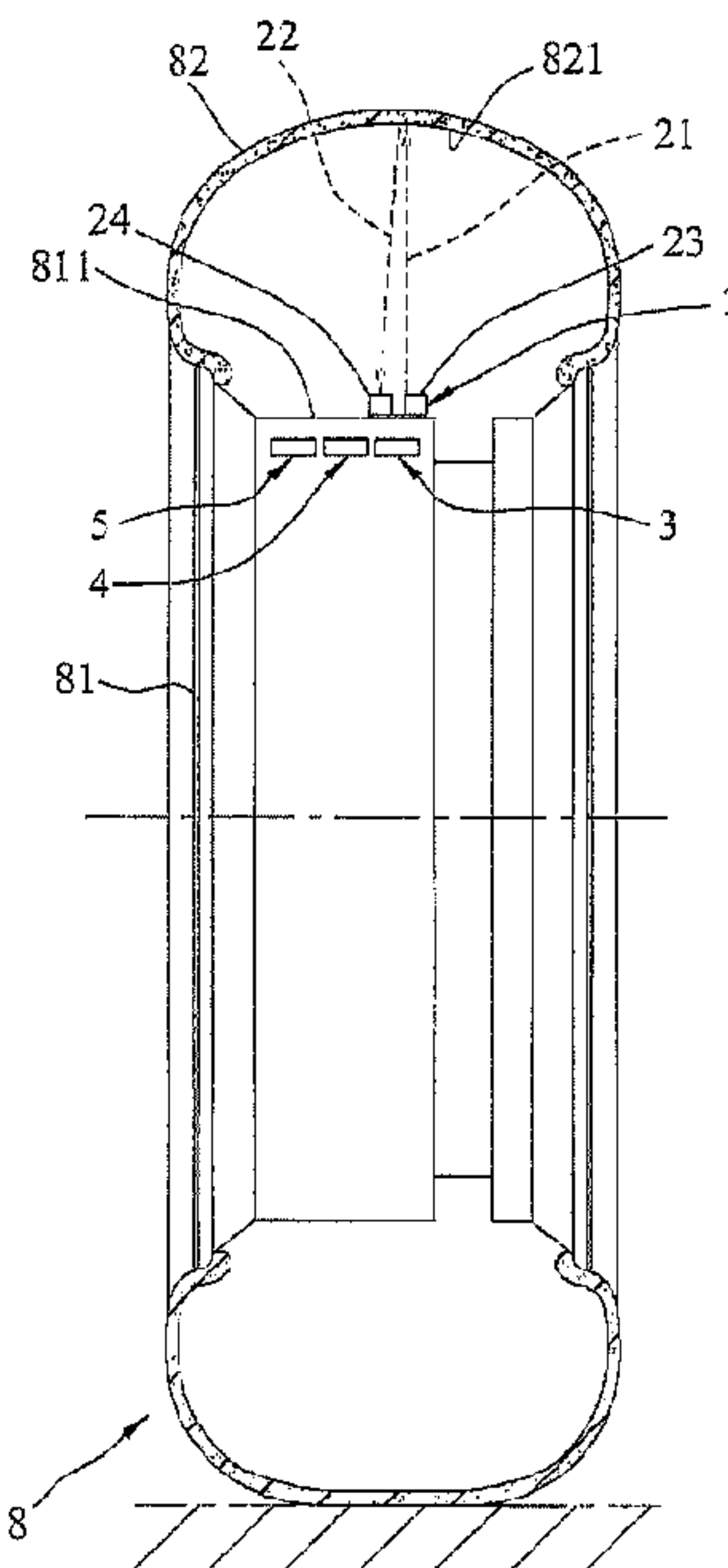




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(54) Titre : SYSTEME DE DETECTION PAR PNEU DE PARAMETRES CINETIQUES
(54) Title: TIRE SENSING SYSTEM OF KINETIC PARAMETERS



(57) Abrégé/Abstract:

A tire sensing system of kinetic parameters is provided, including: at least one wave-emitting source configured to rotate with a tire, and emit at least one detection wave towards an internal surface of said tire; at least one wave sensor configured to rotate with said at least one wave-emitting source, and output a measurement signal according to a physical parameter of said at least one detection wave being reflected off said internal surface; and a processing unit configured to receive said measurement signal, record at least two instants in time during which said at least one detection wave sweeps across the footprint of said tire, and compute a kinetic parameter of said tire with said at least two instants.

ABSTRACT OF THE DISCLOSURE

A tire sensing system of kinetic parameters is provided, including: at least one wave-emitting source configured to rotate with a tire, and emit at least one detection wave towards an internal surface of said tire; at least one wave sensor configured to rotate with said at least one wave-emitting source, and output a measurement signal according to a physical parameter of said at least one detection wave being reflected off said internal surface; and a processing unit configured to receive said measurement signal, record at least two instants in time during which said at least one detection wave sweeps across the footprint of said tire, and compute a kinetic parameter of said tire with said at least two instants.

TIRE SENSING SYSTEM OF KINETIC PARAMETERS

BACKGROUND OF THE INVENTION

Field of the Invention

The present invention is related to a sensing system of kinetic parameters for
5 pneumatic tires, and is particularly related to those depend their operation on both
tire rolling and deflection without actual contact.

Description of the Prior Art

U.S. has issued more than 60 tire deflection or tire footprint related patents
since 1979, only a few of them are similar to the present invention. For examples,
10 U.S. Pat. No.4180794 determines the degree of tire deflection by the quantity of a
light reflecting off its internal surface, and U.S. Pat. No.6612164 detects both the
longitudinal and transverse changes in the position of a measuring point on tire
internal surface, by the reflected radiation of the measuring point.

Another U.S. Pat. No.6967590 measures tire deformation with the optical
15 image of a reflective element disposed on its internal surface, still another Germany
patent No.3916176 measures the distance between wheel rim and tire internal
surface by triangulation. All above patents make use of light reflection of tire
internal surface, none of them takes account of the lateral tilt, which is a significant
part of the whole picture.

20 Accurate, complete yet simple acquisitions of tire kinetic parameters are
certainly the ultimate goal of all related art, but there seems to exist an air of
mystery that has not been fully unveiled, the present invention is therefore such an
attempt trying to fulfill the necessity.

SUMMARY OF THE INVENTION

An aspect of the present invention is to provide a sensing system of kinetic parameters for pneumatic tires. When projecting a detection wave perpendicularly on a point of tire internal surface, rapid and significant changes in the angle of both incidence and deflection, occur every time the point travels across the tire footprint due to tire deflection. By analyzing a signal in inverse proportional to the sum of the two angles, characterization of the tire footprint is achieved with two specific instants and the cyclic period of tire rolling. Based on three specific instants, a longitudinal kinetic parameter being one of frictional force, displacement, and deformation is also revealed.

To achieve the above, a tire sensing system of kinetic parameters is provided, including: at least one wave-emitting source configured to rotate with a tire, and emit at least one detection wave towards an internal surface of said tire; at least one wave sensor configured to rotate with said at least one wave-emitting source, and output a measurement signal according to a physical parameter of said at least one detection wave being reflected off said internal surface; and a processing unit configured to receive said measurement signal, record at least two instants in time during which said at least one detection wave sweeps across said footprint of said tire, and compute a kinetic parameter of said tire with said at least two instants.

The followings explain the present invention in detail, the preferred embodiment is explanatory of the invention and the drawings are illustrative only.

BRIEF DESCRIPTION OF THE DRAWINGS

Fig. 1 is a preferred embodiment of the present invention;

Fig. 2 is the block diagram of said preferred embodiment;

Fig. 3 is a typical example of the light emitter of said preferred embodiment;

Fig. 4 is a typical example of the light receiver of said preferred embodiment;

Fig. 5 is the sectional view of said preferred embodiment operating in the
5 un-deformed region;

Fig. 6 is the sectional view of said preferred embodiment operating at one edge
of the deformed region;

Fig. 7 is the sectional view of said preferred embodiment operating at the other
edge of the deformed region;

10 Fig. 8 and 9 are sectional views of a tire footprint;

Fig. 10 and 11 are typical measurement graphs of said preferred embodiment;

Fig. 12 and 14 are sectional views of two alternative embodiments of the
present invention; and

Fig. 13 is an axially sectional view of a tire having a non-zero lateral tilt.

15 DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENTS

The present invention is a tire sensing system of kinetic parameters, comprises
at least one wave-emitting source, at least one wave sensor and a processing unit.
Said tire has two meanings in this specification, it can be either a pneumatic tire
itself, or an assembled pneumatic wheel that is comprised of both a pneumatic tire
20 and a wheel rim.

Said at least one wave-emitting source is configured to rotate with said tire, and
emit at least one detection wave (directional) towards an internal surface of said tire.
Said at least one wave sensor is configured to rotate with said at least one

wave-emitting source, and output a measurement signal according to a physical parameter of said at least one detection wave being reflected off said internal surface. Said processing unit is configured to receive said measurement signal, record at least two instants in time during which said at least one detection wave sweeps across said footprint of said tire, and compute a kinetic parameter of said tire with said at least two instants. Said kinetic parameter includes a cyclic period of tire rolling. Moreover, said at least two instants in conjunction with said cyclic period of tire rolling leads to five additional kinetic parameters of said tire, which are deflection, born load, footprint area, angular speed and lateral tilt.

10 Figures 1 through 7 represent a preferred embodiment of the present invention. A pneumatic wheel 8 has a wheel rim 81 and a pneumatic tire 82 being assembled on said wheel rim 81 is in contact with the ground. Said wheel rim 81 has an outer rim surface 811, said pneumatic tire 82 has an internal surface 821. Said preferred embodiment comprises a light emitter/receiver module 2, a control processor 3, a
15 power unit 4, a transceiver 5, a pressure sensor 6 and a temperature sensor 7.

In said preferred embodiment, said at least one wave-emitting source and said at least one wave sensor are represented by said light emitter/receiver module 2, said processing unit is represented by said control processor 3. Said at least one wave-emitting source may emit either electromagnetic or sound wave of all
20 frequency, said processing unit can be either internal to or outside of the air chamber of said pneumatic wheel 8, and is functionally coupled to said at least one wave sensor by wires or wirelessly.

Said light emitter/receiver module 2 is coupled to said wheel rim 81, emits a

light beam 21 towards said pneumatic tire 82 and receives a reflected light 22
 returning in the opposite direction from said internal surface 821, also outputs a light
 sensing signal according to said reflected light 22. In said preferred embodiment,
 said at least one detection wave is represented by said light beam 21, said
 5 measurement signal is represented by said light sensing signal. The latter is
 perceived for now but is not limited to as being corresponding to the light quantity of
 said reflected light 22, in other embodiments it is free to stand for any
 energy/intensity/volume related parameter of EM or sound wave.

Said light emitter/receiver module 2 comprises a light emitter 23 for emitting
 10 said light beam 21, and a light receiver 24 for producing said light sensing signal on
 the receiving of said reflected light 22. In said preferred embodiment, said at least
 one wave-emitting source is represented by said light emitter 23, said at least one
 wave sensor is represented by said light receiver 24.

Refer to figures 1,2, and 5, said control processor 3 is coupled to said wheel rim
 15 81 and is electrically connected to both said light emitter 23 and said light receiver
 24, and computes the central angle of tire footprint Θ basing on said light sensing
 signal. The central angle of tire footprint represents the central angle of the flat part
 of tire tread that is in contact with the ground, tire footprint ranges from the tire tread
 having the least to the most and to the least deflection.

20 Refer to figures 1, 3, and 4, said light emitter 23 has an emitting member 231
 for emitting said light beam 21, a lens 232, and a reflective plate 233. In said
 preferred embodiment, said lens 232 is located between said emitting member 231
 and said pneumatic tire 82, said reflective plate 233 is located between said

emitting member 231 and said wheel rim 81.

Said light receiver 24 has an optical-electrical conversion circuit 241 for receiving said reflected light 22 and outputting said light sensing signal, a lens 242, and an optical grating 243. In said preferred embodiment, said lens 242 and said
 5 optical grating 243 are located between said optical-electrical conversion circuit 241 and said pneumatic tire 82.

Said control processor 3 comprises a microprocessor 31 that is electrically connected with said light emitter 23, and a processing circuitry 32, which is electrically connected with both said microprocessor 31 and said light receiver 24.

10 Said power unit 4 is electrically connected to said light emitter/receiver module 2 and said control processor 3.

Said transceiver 5 is electrically connected to said control processor 3. In said preferred embodiment, said transceiver 5 sends and receives messages wirelessly.

Said pressure sensor 6 measures an air pressure of said pneumatic tire 82.

15 Said temperature sensor 7 measures an air temperature of said pneumatic tire 82.

Refer to figures 2, 3, and 5, to start said preferred embodiment, drive said pneumatic wheel 8 to roll forward. Said control processor 3 activates said light emitter 23 to project said light beam 21 onto said internal surface 821, said light
 20 beam 21 is focused by a lens 232 to narrow down its cross sectional area.

Refer to figures 5,6, and 7, when said light beam 21 is projected on the un-deformed region of said pneumatic tire 82, light quantity of said reflected light 22 being received by said light receiver 24 would be at its full maximum; while said

light beam 21 is projected on the deformed region sweeping from the leading edge to the tailing edge, said light receiver 24 would experience an increase followed by an equal decrease on received light quantity in the interval.

Refer to figures 2 and 4, said optical-electrical conversion circuit 241 receives
5 said reflected light 22 to produce said light sensing signal for sending to said processing circuitry 32, where pre-processing, further conversion, and analytical computation of said light sensing signal may be carried out.

Therefore, as said light beam 21 sweeps across the leading edge of tire footprint, said light sensing signal would undergo a rapid fall; as said light beam 21 sweeps
10 across the tailing edge of tire footprint, said light sensing signal would undergo a rapid rise.

Consequently, the respective timings said light beam 21 sweeps across the footprint edges can be identified and recorded by said processing circuitry 32 and said microprocessor 31.

15 Refer to figures 2,6, and 7, said light sensing signal changes dramatically in the shorter interval of deformed region and remains relatively calm in the much longer interval of un-deformed region, so after one tire revolution, said microprocessor 31 distinguishes time interval of the deformed region from that of the un-deformed region, thus the cyclic period of tire rolling and the central angle of tire footprint are
20 determined accordingly.

If a look-up table previously established by laboratory test results is available, techniques such as compensation, interpolation, calibration and the like would be helpful for accuracy enhancement. Said control processor 3 can further transmit the

central angle of tire footprint together with tire pressure/temperature to a vehicle computer (not shown) and/or to be presented to the driver.

Drivers don't stand a chance to react without such a critical information, for the conjunction of normal tire pressure and larger central angle of tire footprint implies
 5 the tire is overloaded, both tire wear and power loss soar in such a situation. On the other hand, normal tire pressure in conjunction with smaller central angle of tire footprint is showing a critical sign of insufficient braking power, a reduction in tire pressure is recommended especially for rainy days.

Further, tire footprint area is well estimated by the central angle of tire footprint
 10 and tire radius/width, tire load would in turn be well estimated by multiplying the footprint area with tire pressure.

Refer to figures 6 to 11, more details of the present invention are explained in the followings. Assume a loaded tire is rolling forward on a ground plane, its rotation axis is parallel to the plane. Refer to figures 8 and 9 for the following definitions of
 15 said loaded tire:

Footprint is the rectangular plane ABCD having an area of A_{bcd} ;

Leading footprint edge is line AB;

Tailing footprint edge is line CD;

Rotation axis is Axis;

20 Perpendicularly projected line of Axis on plane ABCD is line EF;

Longitudinal direction is X;

Normal direction of plane ABCD is Z, tire deflection is ΔZ ;

Central circumference of tire internal surface is I;

Tire geometric center is Center;

Width W is the length of line AB, CD, or EF;

Tire radius is R ;

G is the point of reflection on I ;

5 H is a reference point of the wheel rim on line Center to G ;

The N th-cycle angular speed is $\omega(N)$;

The N th-cycle cyclic period of rolling is $\text{Period}(N)$;

The N th time arrow HG intersects line AB occurs at time $T_{\text{toe}}(N)$;

The N th time arrow HG intersects line EF occurs at time $T_{\text{sole}}(N)$;

10 The N th time arrow HG intersects line CD occurs at time $T_{\text{heel}}(N)$;

The N th-cycle central angle formed by line AB and CD is $\Theta_{\text{sole}}(N)$;

The N th-cycle central angle formed by line AB and EF is $\Theta_{\text{toe}}(N)$;

The N th-cycle central angle formed by line CD and EF is $\Theta_{\text{heel}}(N)$;

The angle between arrow GH and the direction of strongest wave reflection at G is

15 $\Theta_{\text{dev}}(T)$.

Set up at least one wave-emitting source and at least one wave sensor at H , said at least one wave-emitting source and said at least one wave sensor are in close proximity to each other. Said at least one wave-emitting source emits at least one detection wave of small cross sectional area towards G , said at least one wave sensor
20 receives the return wave of said at least one detection wave being reflected off G , and outputs a measurement signal according to an energy/intensity/volume related parameter of said return wave.

G can be either a point of tire internal surface, or a reflective element 83 that

adheres to said internal surface. It is preferred for said internal surface or said reflective element 83 to possess consistent and smooth surface, so that the strongest or the most possible direction in which said at least one detection wave deflects at G, remains unchanged if G were a perfect reflective coating. Assume said internal surface is symmetrical about I, a typical example of $\Theta_{dev}(T)$ is illustrated in figure 10 given $\omega(N)$ is constant.

Since the sign of $\Theta_{dev}(T)$ does not matter to any energy/intensity/volume related parameter of said return wave, therefore the absolute value of $\Theta_{dev}(T)$ results in both a local extreme and a local time-rate extreme of change, not only at both $T_{toe}(N)$ and $T_{heel}(N)$ but also at $T_{sole}(N)$.

Said measurement signal can be optimized by adjusting cross sectional area of said at least one detection wave according to both surface smoothness of G and the distance from H to G, and/or selecting physics and frequency of said at least one detection wave according to the material and reflectivity of G. A typical example of said measurement signal is illustrated in figure 11, in which an infrared laser beam was projected on the internal surface of a 185/65R14 tire itself, and the measurement signal was corresponding to the light quantity of said return wave received at H by an infrared light sensor.

Further, set up a processing unit. Said processing unit receives said measurement signal, has hardware and software combined capability of computation, is capable of tagging an event to its own time base and storing/recording relevant data in its memory, is also capable of identifying at least one of a local extreme and a local time-rate extreme of change associated with said measurement signal.

Whenever an extra accelerometer is available, whether electrically coupled to or embedded in said processing unit, either or both of $\omega(N)$ and $\text{Period}(N)$ can be derived from said accelerometer with said computation.

For instance, said processing unit might have recorded two instants $T_{\text{toe}}(N)$ and $T_{\text{heel}}(N)$ in one case, and have already derived $\text{Period}(N)$ with said accelerometer in existence, the central angle of tire footprint Θ (which equals $\Theta_{\text{sole}}(N)$ at here) is defined by the two instants and $\text{Period}(N)$ in this case:
 $\Theta_{\text{sole}}(N) = 360^\circ \cdot (T_{\text{heel}}(N) - T_{\text{toe}}(N)) / \text{Period}(N)$. Suppose in another case three instants $T_{\text{toe}}(N)$, $T_{\text{heel}}(N)$ and $T_{\text{toe}}(N+1)$ were recorded, obviously $\text{Period}(N)$ is self-contained in the three instants:

$$\Theta_{\text{sole}}(N) = 360^\circ \cdot (T_{\text{heel}}(N) - T_{\text{toe}}(N)) / (T_{\text{toe}}(N+1) - T_{\text{toe}}(N)).$$

Suppose in still another case said processing unit recorded $T_{\text{toe}}(N)$, $T_{\text{sole}}(N)$, $T_{\text{heel}}(N)$, $T_{\text{toe}}(N+1)$, $T_{\text{sole}}(N+1)$ and $T_{\text{heel}}(N+1)$ sequentially, then $\text{Period}(N)$ is averaged by:

$\text{Period}(N) = ((T_{\text{heel}}(N+1) - T_{\text{heel}}(N)) \cdot (T_{\text{toe}}(N+1) - T_{\text{toe}}(N)))^{0.5}$, the same principle applies to $\Theta_{\text{sole}}(N)$:

$$\Theta_{\text{sole}}(N) = 360^\circ \cdot ((T_{\text{heel}}(N+1) - T_{\text{toe}}(N+1)) \cdot (T_{\text{heel}}(N) - T_{\text{toe}}(N)))^{0.5} / \text{Period}(N).$$

Similarly, $\Theta_{\text{toe}}(N)$ and $\Theta_{\text{heel}}(N)$ are all concluded in this way.

Even the tire is not rolling at a constant speed, since a typical family saloon advances at most 2.5 meters on one wheel-revolution, once a certain speed is reached so that $\omega(N)$ and $\omega(N+1)$ can be regarded to have the same acceleration, then the above 2 equations could actually be a very good guess. A numerical evaluation of a race car is demonstrated herein, assume the angular travel in one of

the wheels is: $\Theta_{\text{travel}}(T) = 1389 \cdot T^2 + 1000 \cdot T$, and further assume $\Theta_{\text{sole}}(N) = 20^\circ$ and $T_{\text{toe}}(1) = 0 \text{Sec}$. First solve T for $\Theta_{\text{travel}}(T) = 20^\circ, 360^\circ, 380^\circ, 720^\circ, 740^\circ, 1080^\circ$, and 1100° , next by substituting these answers into the last two equations, the estimated results are: $\text{Period}(1) = 0.2595 \text{Sec}$, $\Theta_{\text{sole}}(1) = 20.8^\circ$; $\text{Period}(2) = 0.1802 \text{Sec}$,

5 $\Theta_{\text{sole}}(2) = 20.2^\circ$; $\text{Period}(3) = 0.1468 \text{Sec}$, and $\Theta_{\text{sole}}(3) = 20.0^\circ$.

Therefore, $\text{Abcd} = 2 \cdot W \cdot R \cdot \sin(\Theta_{\text{sole}}(N)/2)$, $\Delta Z = R \cdot (1 - \cos(\Theta_{\text{sole}}(N)/2))$,
 $\omega(N) = 360^\circ / \text{Period}(N)$.

It takes the tire's carcass spring constant $K_{\text{carcass}}(\Delta Z)$ other than tire pressure P alone to compute tire load L more precisely: $L \approx P \cdot \text{Abcd} + \Delta Z \cdot K_{\text{carcass}}(\Delta Z)$. The
 10 latter can be input to said processing unit by wire or wirelessly after scanning the barcode of a specific tire, or by using an established data bank stored in the memory of said processing unit once a specific tire's RFID is recognized.

Similarly, longitudinal frictional force $F(N)$ is derived by modeling a tire deformation in one direction as a displacement in that direction of an equivalent
 15 spring: $F(N) = (\Theta_{\text{heel}}(N) / \Theta_{\text{toe}}(N) - 1) \cdot K(P, L, \Theta_{\text{heel}}(N) / \Theta_{\text{toe}}(N))$, thus $\Theta_{\text{heel}}(N) / \Theta_{\text{toe}}(N)$ can be regarded as the longitudinal displacement or deformation related factor in the equivalent spring model.

During braking the ground exerts a great force on the tire so that $\omega(N)$ can change instantly, at this moment said processing unit has to record consecutive sets
 20 of $T_{\text{toe}}(N)$, $T_{\text{sole}}(N)$, and $T_{\text{heel}}(N)$, and compute on a cycle-by-cycle basis for the highest possible update rate according to the following:

$$\Theta_{\text{heel}}(N) / \Theta_{\text{toe}}(N) = (T_{\text{heel}}(N) - T_{\text{sole}}(N)) / (T_{\text{sole}}(N) - T_{\text{toe}}(N)).$$

Said accelerometer has many more benefits in the present invention, it enables

said processing unit to wake up to a braking deceleration for power saving while keeping alert, the accompanied self-check and calibration capabilities are also essential to make a system more complete.

Though it is preferred for said processing unit to acquire complete sets of
 5 Ttoe(N), Tsole(N), and Theel(N) more than one tire revolution, sometimes due maybe to poor road conditions, for instance, it is possible only Tsole(N), Ttoe (N+1) and Ttoe (N+2) were recorded in several consecutive revolutions. Even so, still the following estimations work well in general:

$$\text{Period}(N+1) = \text{Ttoe}(N+2) - \text{Ttoe}(N+1),$$

$$10 \quad \Theta_{\text{sole}}(N+1) = 720^\circ \cdot (\text{Period}(N+1) + \text{Tsole}(N) - \text{Ttoe}(N+1)) / \text{Period}(N+1).$$

To operate in diverse road conditions, said processing unit should be built in a number of strategies, as whether to acquire more data sets for averaging new results with the old, to keep on the recording/computing/screening process until tire speed stabilizes, to listen and response to the control from the vehicle, or simply to enter a
 15 sleep mode temporarily, etc.

Refer to figure 12 for the determination of tire lateral tilt. Said at least one wave-emitting source is located at H and is projecting said at least one detection wave in a line pattern on said internal surface, said line pattern is in parallel with Axis. Set up 2 points of reflection both G1 and G2 on said internal surface, both G1
 20 and G2 are symmetrical about I. Further, set up two wave sensors on both sides of H that are in parallel with Axis and symmetrical about H, said two wave sensors receive respectively on said return wave being reflected off both G1 and G2 and output respective measurement signals. Said processing unit receives said

measurement signals to compute the central angles of tire footprint on both the inner and outer sides respectively.

As a tire tilts laterally, its central angle of tire footprint becomes larger on one side and smaller on the other side, figure 13 represents an axially sectional view of such a condition, both the solid and dotted triangles are formed by each central angle of tire footprint intersecting with said internal surface. Said processing unit further computes said lateral tilt with central angles of tire footprint on both inner and outer sides, or simply look it up in an established data bank of corresponding tests.

Figure 14 shows an alternative embodiment for lateral tilt, two sets of wave-emitting source and wave sensor are located at H1 and H2 respectively with corresponding points of reflection being G1 and G2 respectively, both H1 and H2 are irrelevant. Said two sets of wave-emitting source and wave sensor function independently to project individual detection waves on corresponding points of reflection, receive said return wave by respective wave sensors respectively, and output measurement signals respectively. Said processing unit receives said measurement signals to compute the central angles of tire footprint on both the inner and outer sides respectively. Said processing unit further computes said lateral tilt or simply look it up in an established data bank of corresponding tests.

It is preferred for the present invention to incorporate a transceiver and a display unit, tire kinetic parameters are essential to not only drivers but also vehicle control systems such as ABS and ESP for next-level driving safety.

Although particular embodiments of the present invention are disclosed in detail for the purposes of illustration, various modifications and enhancements may

be made without departing from the spirit and scope of the present invention.

Accordingly, the invention is not to be limited except as by the appended claims.

WHAT IS CLAIMED IS:

1. A tire sensing system of kinetic parameters, including:
 - at least one wave-emitting source configured to rotate with a tire, and emit
 - at least one detection wave towards an internal surface of said tire;
 - 5 at least one wave sensor configured to rotate with said at least one wave-emitting source, and output a measurement signal according to a physical parameter of said at least one detection wave being reflected off said internal surface; and
 - a processing unit configured to receive said measurement signal, record at
 - 10 least two instants in time during which said at least one detection wave sweeps across the footprint of said tire, and compute a kinetic parameter of said tire with said at least two instants.
2. The tire sensing system of kinetic parameters of claim 1, wherein said processing unit records three instants in time during which said at least one
- 15 detection wave sweeps across said footprint of said tire, said processing unit computes a longitudinal kinetic parameter of said tire with said three instants, and said longitudinal kinetic parameter is one of frictional force, displacement and deformation.
3. The tire sensing system of kinetic parameters of claim 1, wherein said
- 20 processing unit identifies at least one of a local extreme and a local time-rate extreme of change associated with said measurement signal, and records at least one of two instants associated with said local extreme and said local time-rate extreme of change.

4. The tire sensing system of kinetic parameters of claim 1, further including a reflective element, wherein said reflective element adheres to said internal surface.
5. The tire sensing system of kinetic parameters of claim 1, wherein said processing unit computes a central angle of tire footprint with said at least two instants and a cyclic period of said tire.
6. The tire sensing system of kinetic parameters of claim 1, wherein said at least two instants are recorded in one revolution of said tire.
7. The tire sensing system of kinetic parameters of claim 5, wherein said processing unit identifies at least one of a local extreme and a local time-rate extreme of change associated with said measurement signal, and records at least one of two instants associated with said local extreme and said local time-rate extreme of change.
8. The tire sensing system of kinetic parameters of claim 5, further including a reflective element, wherein said reflective element adheres to said internal surface.
9. The tire sensing system of kinetic parameters of claim 5, wherein two wave sensors are configured to rotate with said at least one wave-emitting source and output two measurement signals, said processing unit receives said two measurement signals and computes a lateral tilt of said tire.
10. The tire sensing system of kinetic parameters of claim 9, wherein said processing unit identifies at least one of a local extreme and a local time-rate extreme of change associated with said two measurement signals,

and records at least one of two instants associated with said local extreme
and said local time-rate extreme of change.

11. The tire sensing system of kinetic parameters of claim 9, further including a
reflective element, wherein said reflective element adheres to said internal
surface.

5

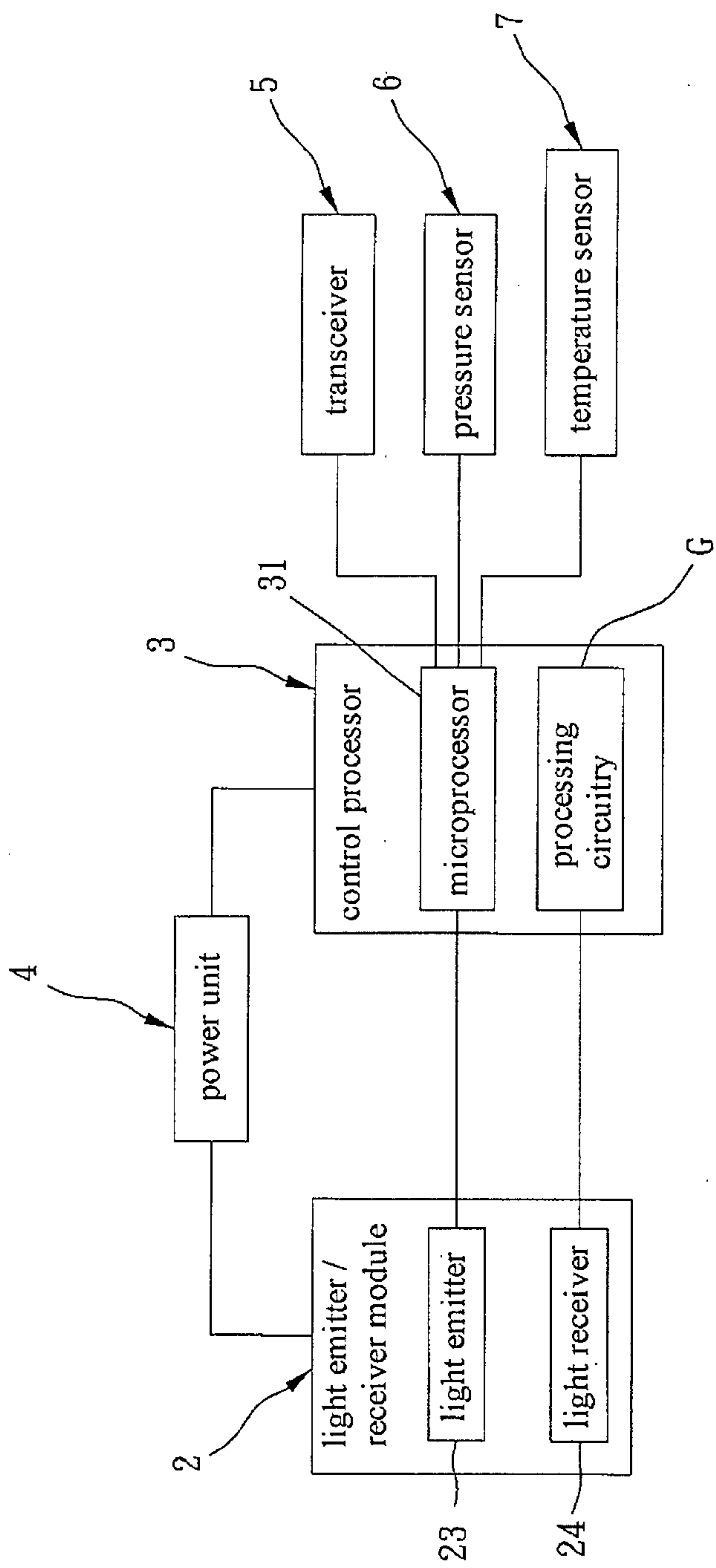


FIG. 2

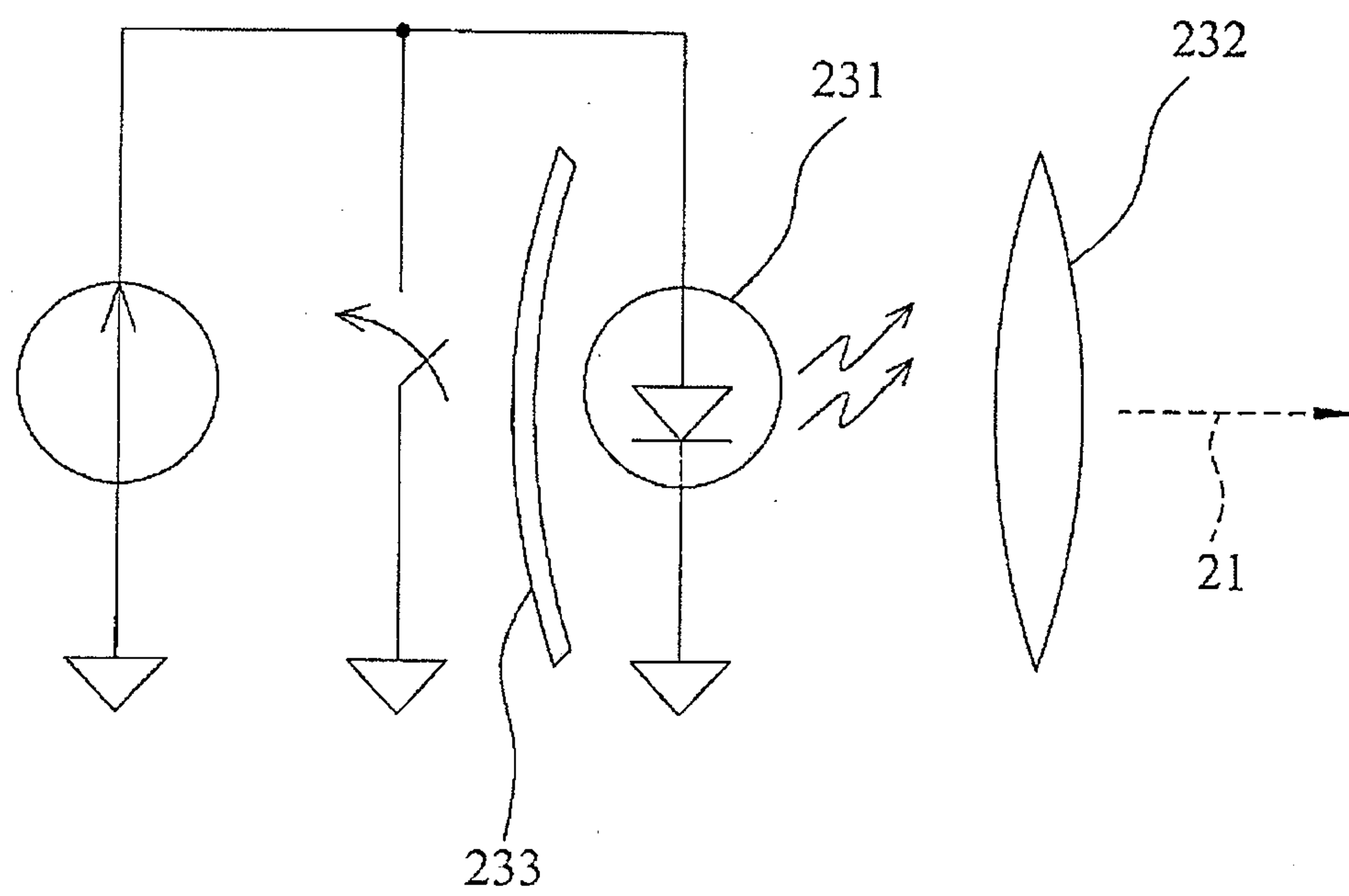


FIG. 3

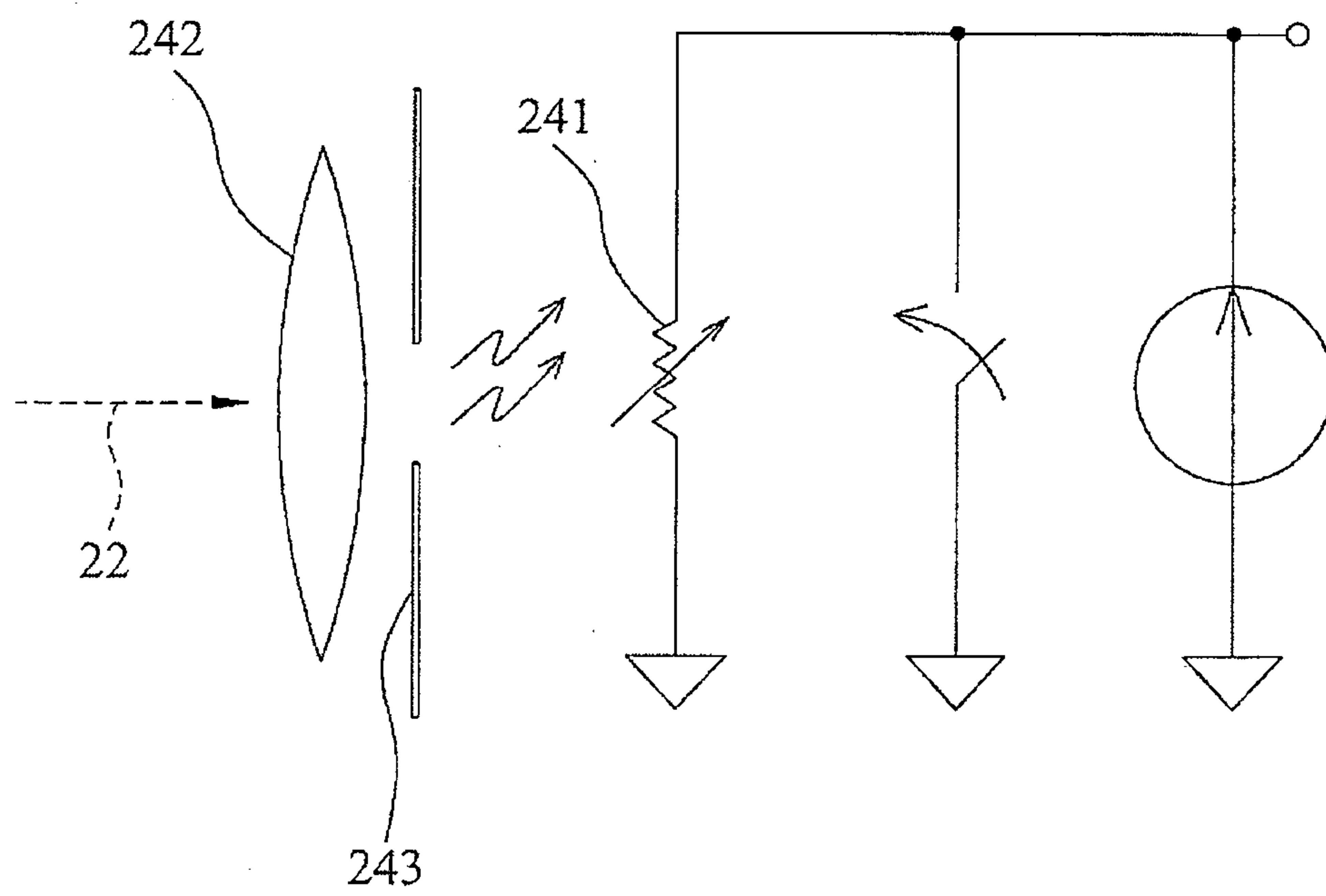


FIG. 4

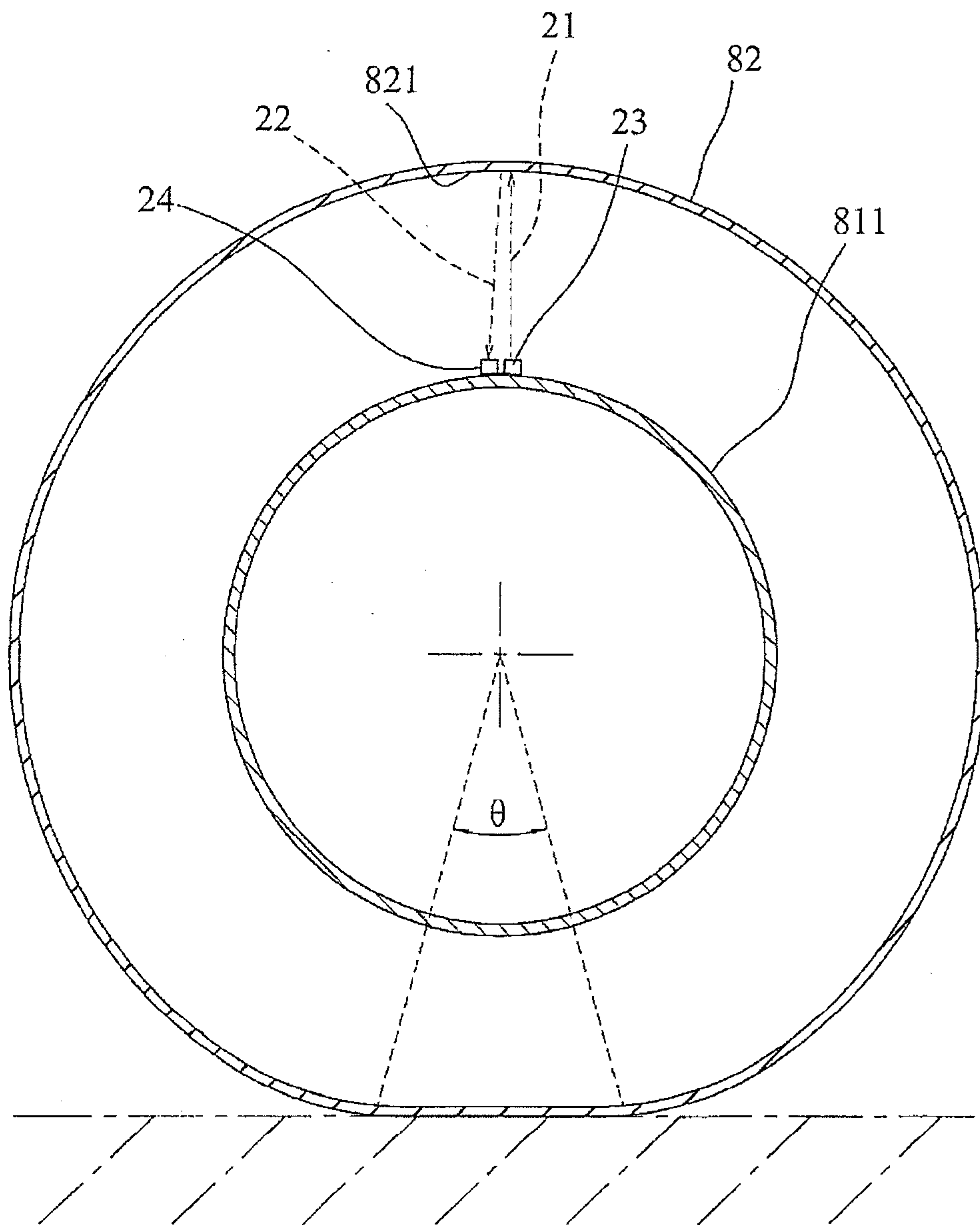


FIG. 5

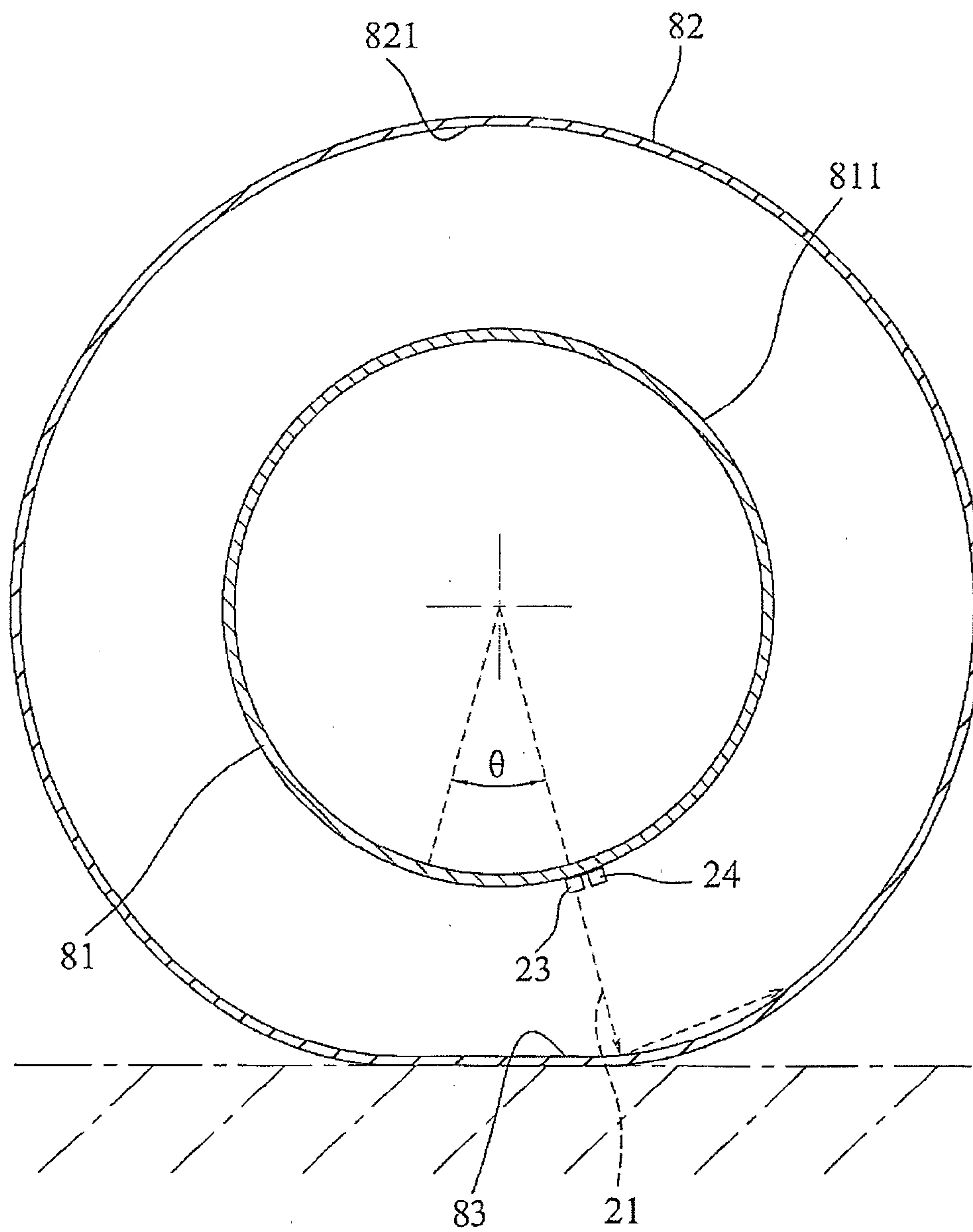


FIG. 7

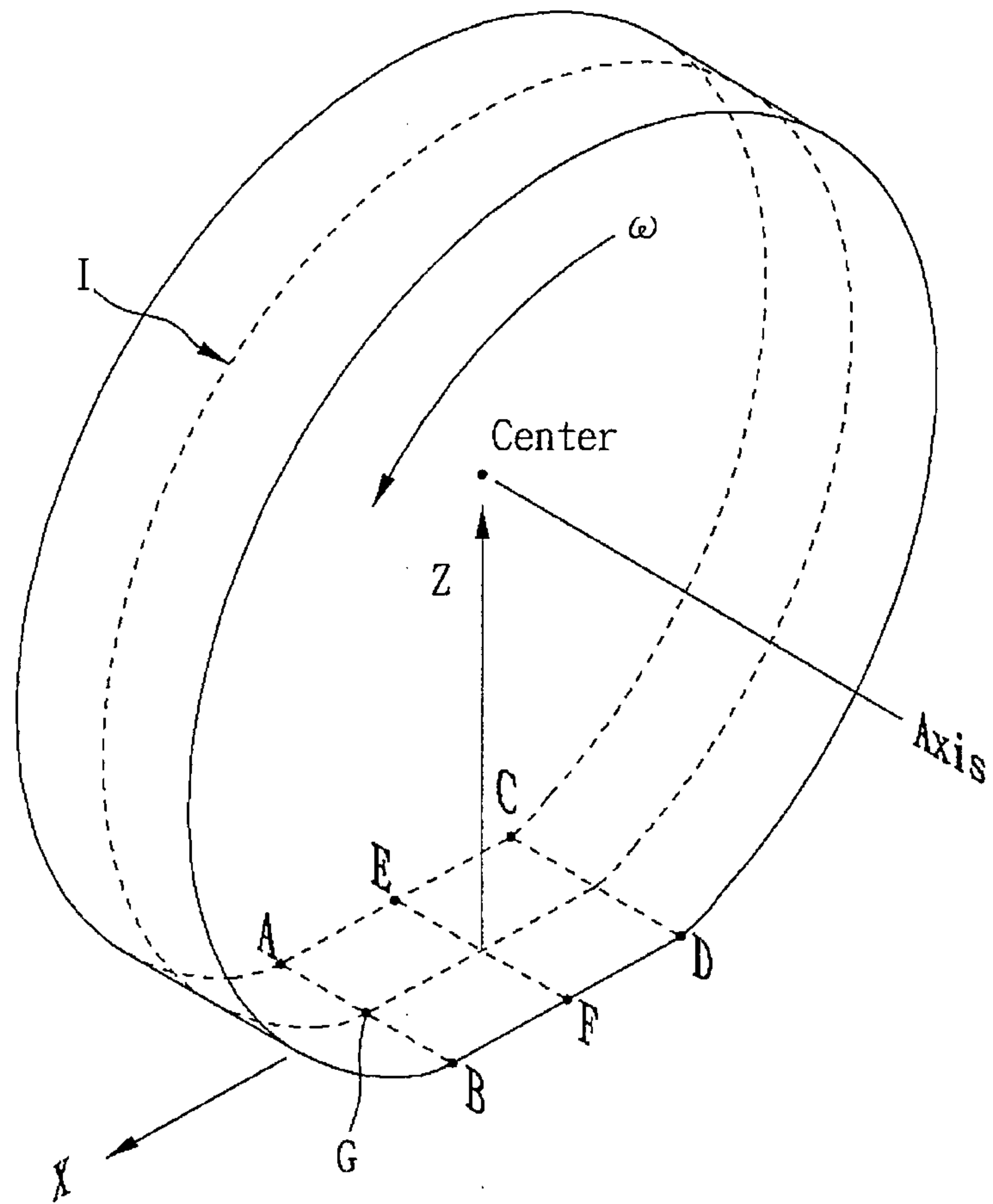


FIG. 8

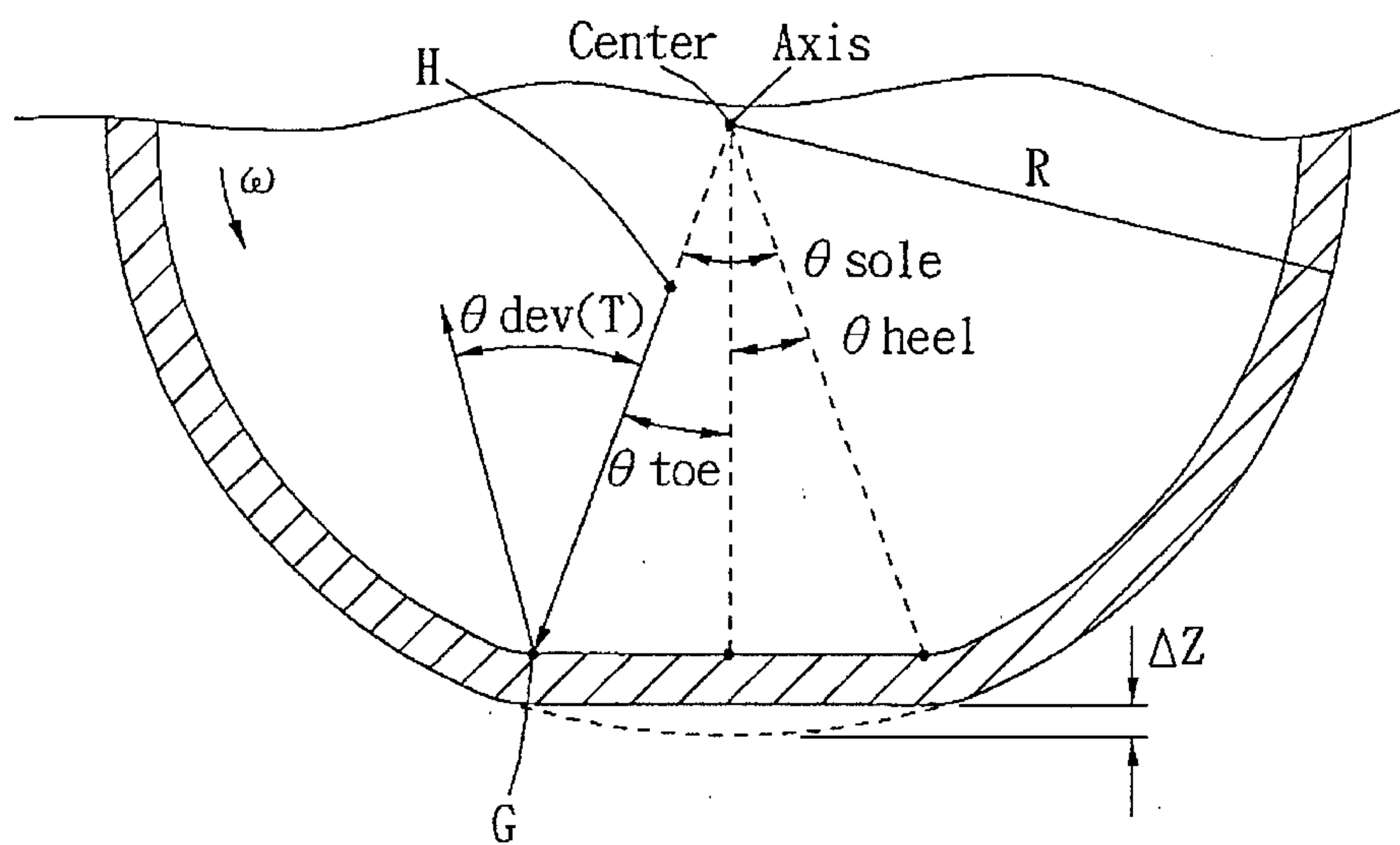


FIG. 9

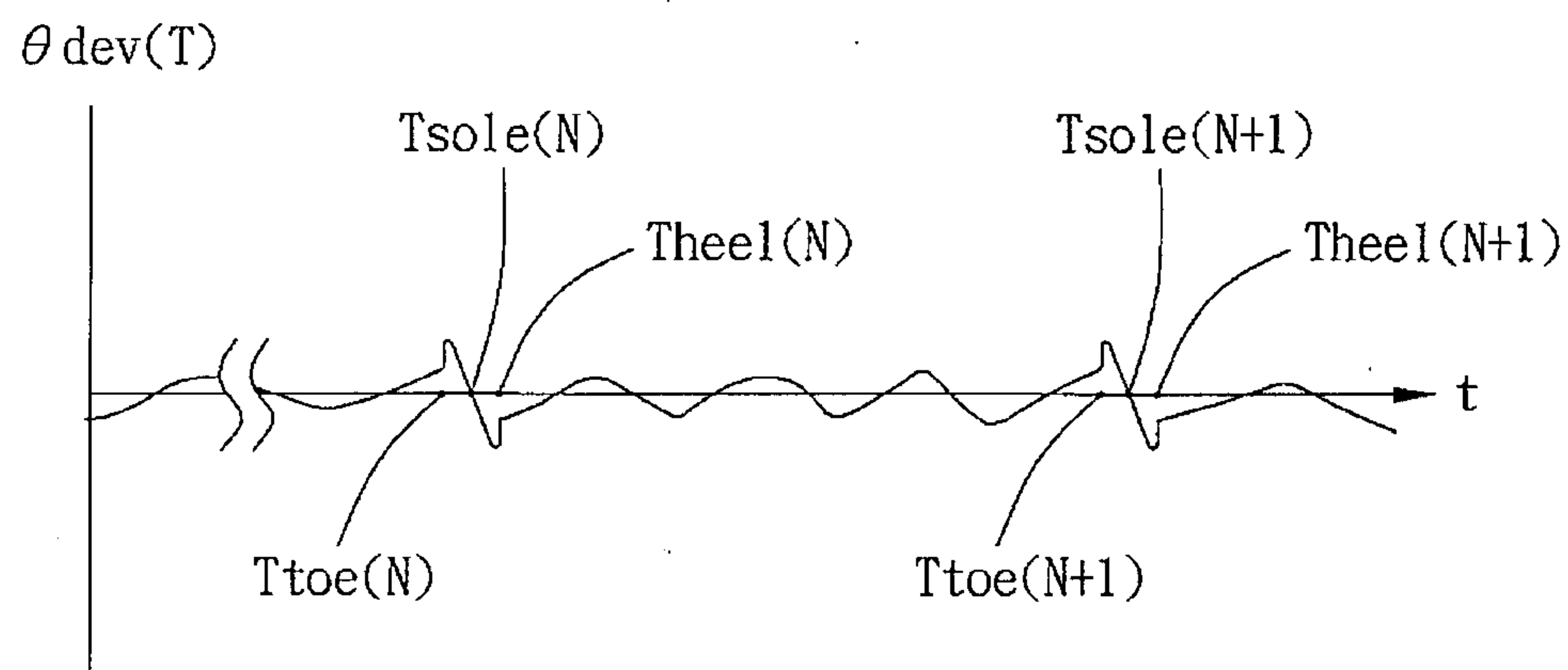


FIG. 10

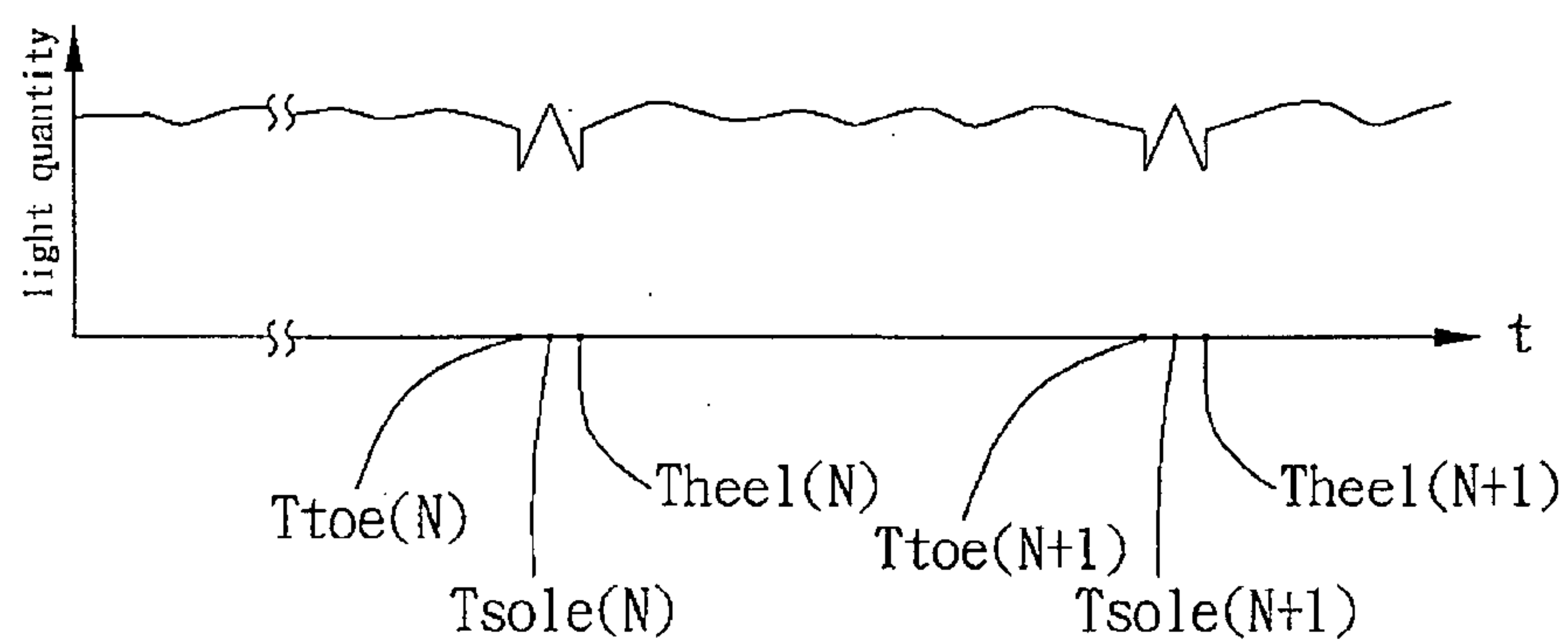


FIG. 11

----- Axis

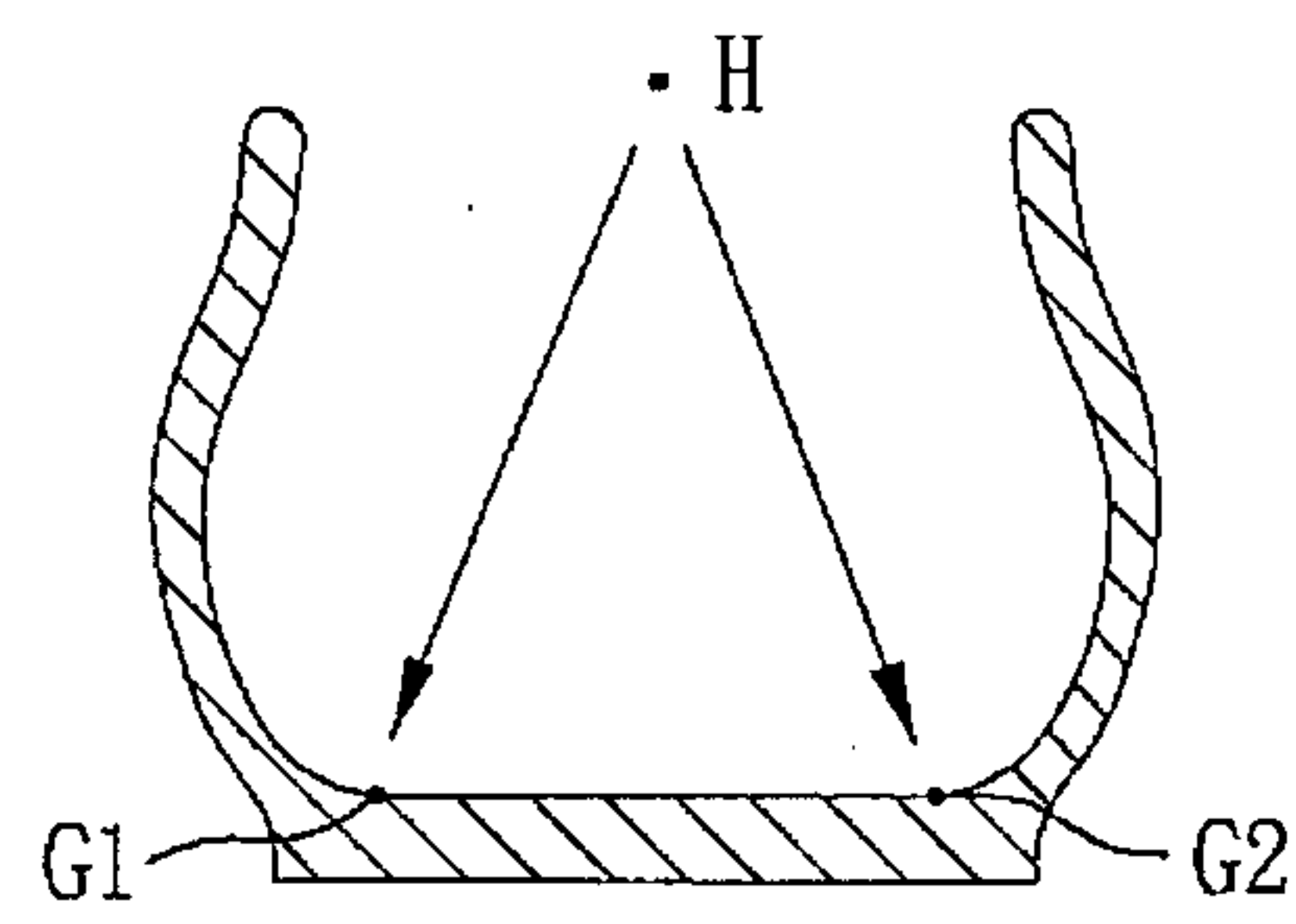


FIG. 12

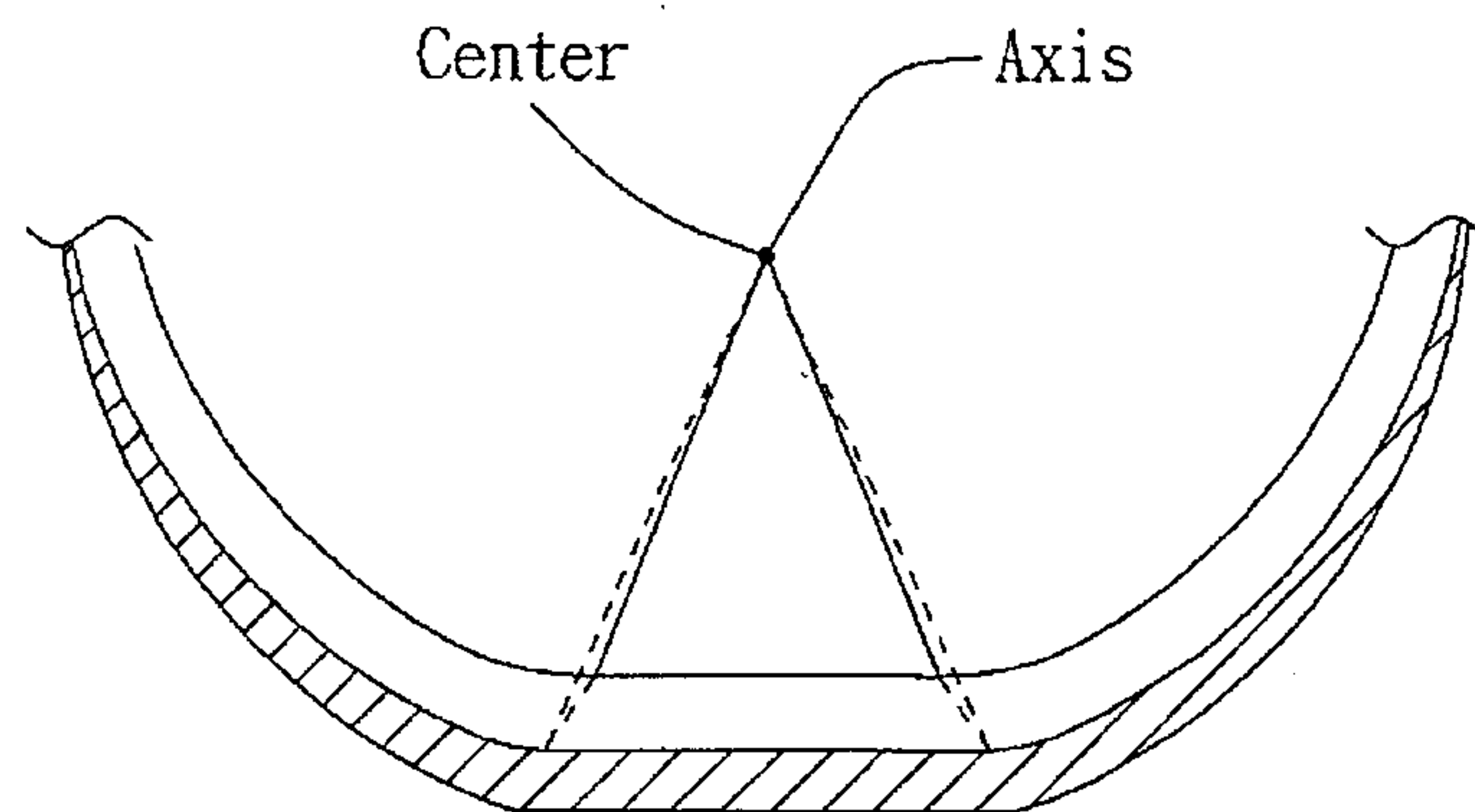


FIG. 13

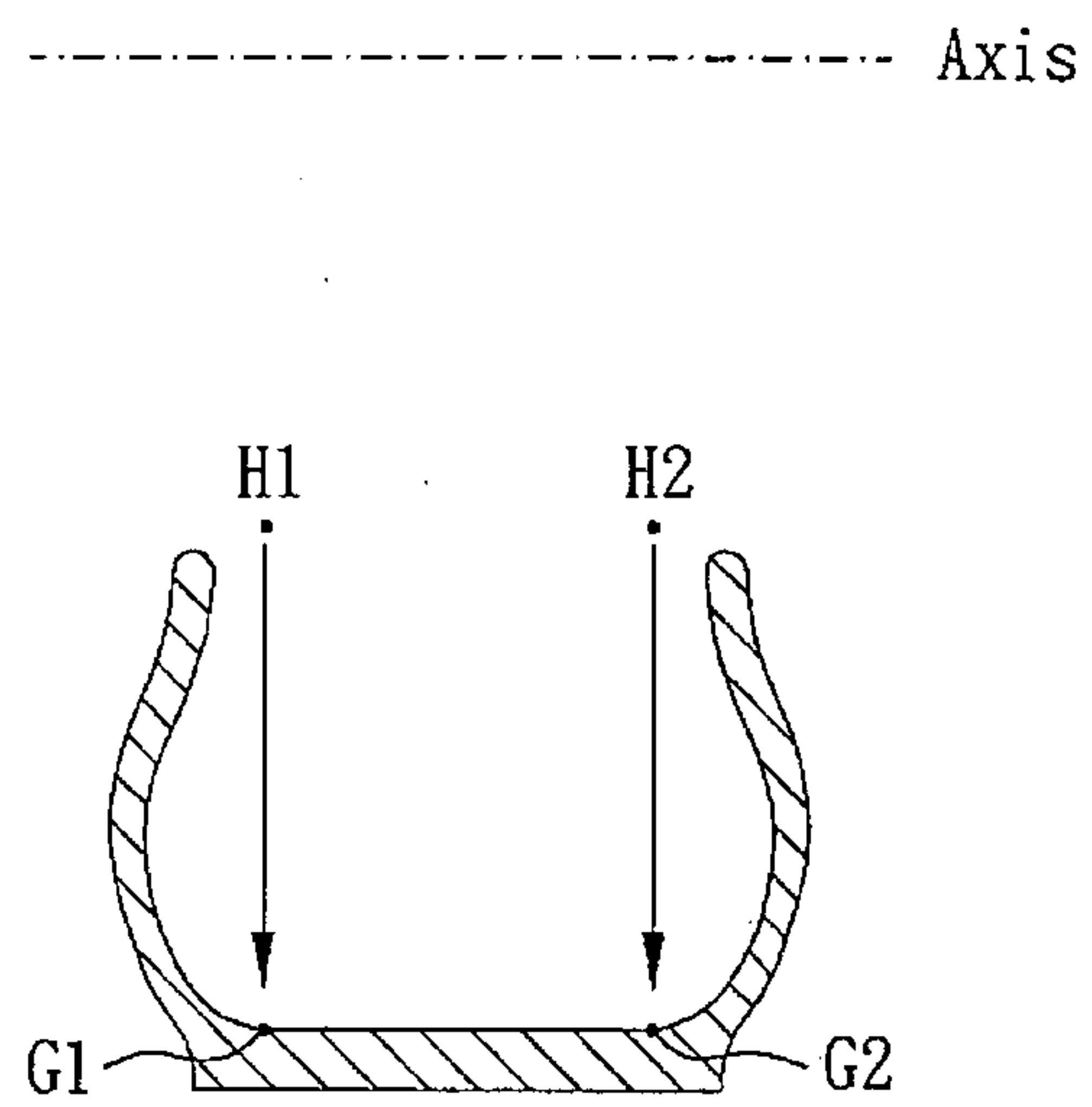


FIG. 14

