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(54) **Titre : SYSTEME DE SIEGE DE VEHICULE ET PROCEDE DE REDUCTION DE LA FATIGUE AU MOYEN D'UN MOUVEMENT
D'ACTIONNEUR DYNAMIQUE**
 (54) **Title: VEHICLE SEATING SYSTEM AND METHOD FOR REDUCING FATIGUE WITH DYNAMIC ACTUATOR MOVEMENT**

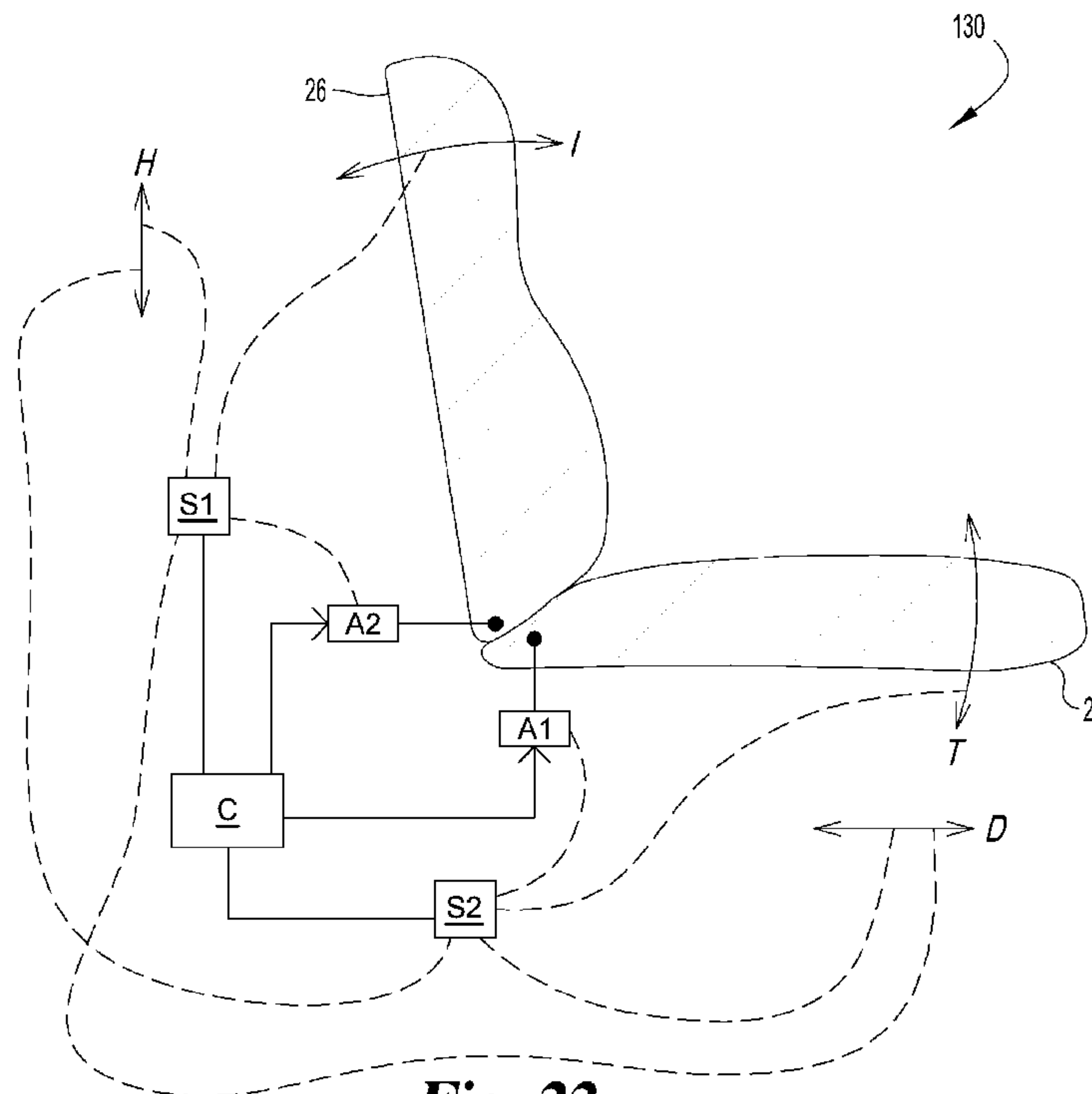


Fig. 22

(57) **Abrégé/Abstract:**

A vehicle seating system is disclosed having a seat and at least one powered seat adjustment actuator for altering the seating position formed by the seat. A controller dynamically adjusts the speed of movement of said seat back based on comparing at least

(57) Abrégé(suite)/Abstract(continued):

one speed parameter from said first series of speed parameters with a first smooth movement speed projection and dynamically adjusting a first control signal to said first powered seat adjustment actuator to converge the speed of movement toward or equal to said first smooth movement speed projection.

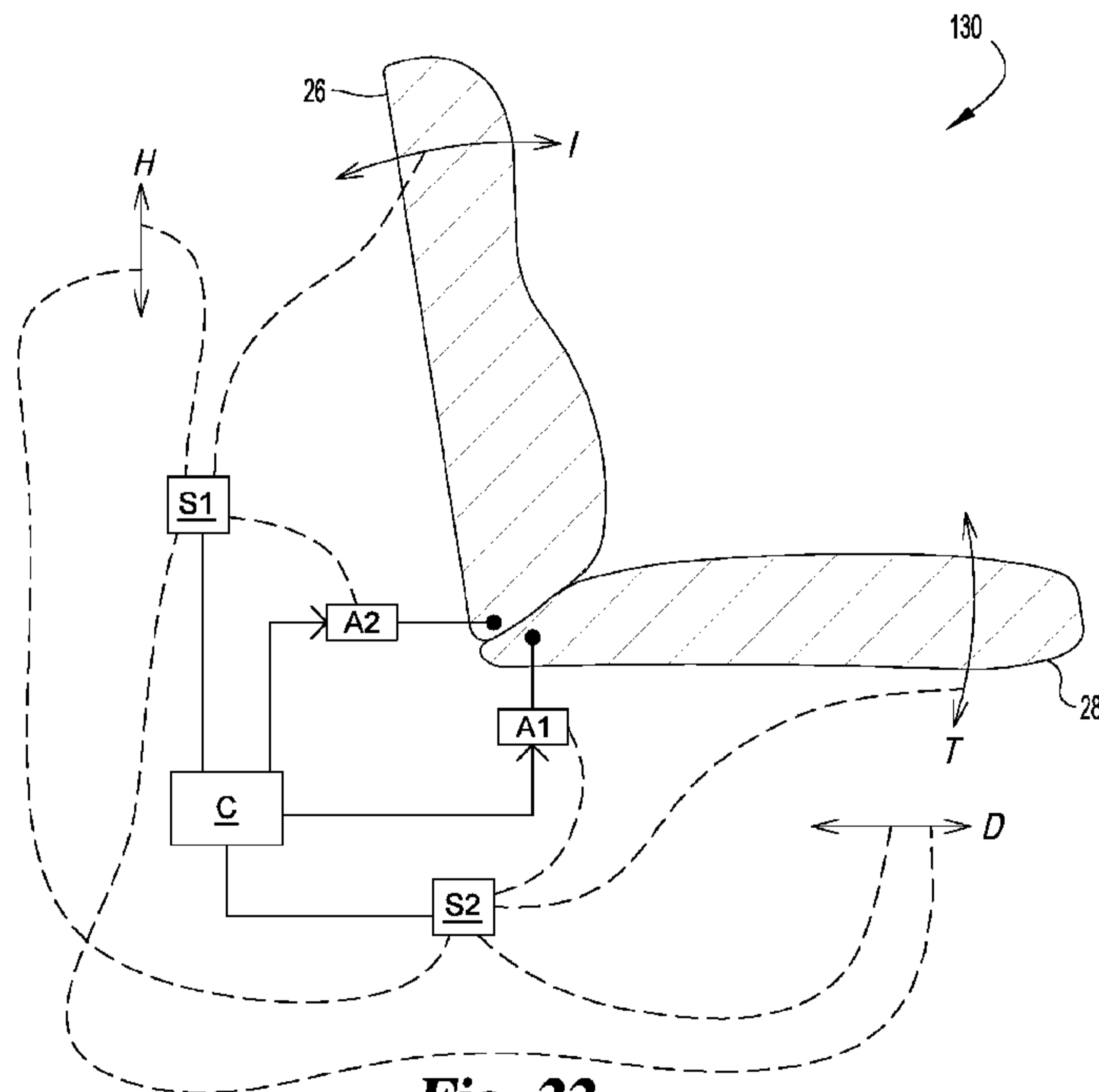
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[Continued on next page]

(54) **Title:** VEHICLE SEATING SYSTEM AND METHOD FOR REDUCING FATIGUE WITH DYNAMIC ACTUATOR MOVEMENT**Fig. 22**

(57) **Abstract:** A vehicle seating system is disclosed having a seat and at least one powered seat adjustment actuator for altering the seating position formed by the seat. A controller dynamically adjusts the speed of movement of said seat back based on comparing at least one speed parameter from said first series of speed parameters with a first smooth movement speed projection and dynamically adjusting a first control signal to said first powered seat adjustment actuator to converge the speed of movement toward or equal to said first smooth movement speed projection.

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With or without some or all of those features, it can be beneficial to alter the nature of slow movement of a seat depending on driving conditions and/or locations (for example fast vs. slow; city vs. highway, or otherwise) by multiple modes of operation, various degrees of speed, frequency and/or amplitude, both, or
5 otherwise.

There is a need for improved vehicle systems and methods. Certain embodiments address these and other needs.

SUMMARY OF THE DISCLOSURE

In one aspect of the present disclosure, a system comprises a vehicle seating system including a seat and at least one powered seat adjustment actuator for altering the seating position formed by the seat.

5 It is a vehicle system or method involving one or more seat adjustment actuators to slowly move the seat for reducing user fatigue, and includes dynamically adjusting seat actuator speed for smoothness.

The invention is set forth by the claims, and it is not limited by the foregoing.

10 It is an object of certain embodiments to provide an improved vehicle seating system and method.

DESCRIPTION OF THE DRAWINGS

Fig. 1A is a side view of a vehicle seat and a user seated therein.

Fig. 1B is a side, partial cross-sectional view of a vehicle seating system embodiment.

5 Fig. 1C is a side, partial cross-sectional view of a vehicle seating system embodiment.

Fig. 1D is a side, partial cross-sectional view of a vehicle seating system embodiment.

10 Fig. 2A is a side, partial cross-sectional view of a vehicle seating system embodiment.

Fig. 2B is a perspective view of an example vehicle braking system.

Fig. 3A is one example of two actuator movement profiles in a first mode.

Fig. 3B is one example of two actuator movement profiles in a second mode.

15 Fig. 4 is a profile of one example of variable actuator speed.

Fig. 5A is one example of an actuator movement profile.

Figs. 5B-5E are variations of an actuator movement profile as compared to Fig. 5A.

20 Figs. 6-16 are other of various examples of movement profiles of a vehicle seating system.

Figs. 17-18 are graphic illustrations of further examples of condition profiles of a vehicle seating system.

Fig. 19 is a flow diagram of a vehicle seating system according to an embodiment of the present disclosure.

25 Fig. 20 is a flow diagram of a vehicle seating system according to an embodiment of the present disclosure.

Fig. 21 is a side, partial cross-sectional view of a vehicle seating system embodiment with sensors for dynamic actuator movement.

30 Fig. 22A-D are graphic illustrations of examples of smooth movement speed projections and series of speed parameters.

5

Fig 23A is a graphic illustration of an example of a pulse width modulated signal.

Fig 23B is a graphic illustration of an example of a hall effect sensor output.

5 Fig 23C is a graphic illustration of an example of a pulse width modulated signal in response to a hall effect sensor output.

BRIEF DESCRIPTION OF THE ILLUSTRATED EMBODIMENTS

While the present disclosure may be embodied in many different forms, for the purpose of promoting an understanding of the principles of the disclosure, reference will now be made to the embodiments illustrated in the drawings and specific language will be used to describe the same. It will nevertheless be understood that no limitation of the scope of the disclosure is thereby intended. Any alterations and further modifications in the described embodiments, and any further applications of the principles of the disclosure as described herein are contemplated as would normally occur to one skilled in the art to which the disclosure relates.

Various embodiments of the system can be used within automobiles, trains, and/or airplanes, as examples.

The one or more actuators are moveable to alter the seating position formed by the seat, to provide comfort to the user and/or reduce positional fatigue and other effects of long distance traveling. The actuators may be independently activated by a user and/or may be automatically activated by the electrical controller. The following are hereby incorporated by reference: U.S. Patent No. 7,422,285, U.S. Patent No. 7,566,096, U.S. Patent Application Publication No. 2008/0091322 and U.S. Patent Application Publication No. 2009/0005938.

Regarding automatic activation, the actuators reposition the seat to different seating positions with a slow movement average of typically less than about 15 centimeters per second, and often less than about 10 centimeters per second. The electrical controller may have a control period which generally includes at least one movement period and, in certain embodiments, at least one stationary period. In certain embodiments, the electrical controller includes controlling software which may be initially activated by a user at a desired time to begin automatic movement of the actuators. Thereafter, the control period preferably includes at least one movement period where the actuators automatically move to alter the seat position of the seat (through one or more different seating positions) and reposition the user to reduce long distance traveling fatigue.

For general overview purposes, Fig. 1A illustrates a vehicle user 20 seated in a vehicular seat 22. A typical vehicular seat includes a head rest 24, a seat back 26, and a seat bottom 28. As illustrated in Fig. 1A, the user is operating a motor vehicle by using a typical steering wheel and pedal system. Additionally, the motor vehicle may include a typical vehicle braking system, such as system 200 (Fig. 2B) as an example.

As exemplified in Figs 2A and 2B, system 200 generally includes a brake pedal 202 leading to a master cylinder 204. Hydraulic lines 206 lead from master cylinder 204 to typical disc brakes 208. Upon a vehicle/user event, such as for example activation of vehicle braking system 200, disc brakes 208 operate in a typical fashion to stop the rotation of front wheels 209. Hydraulic line 210 leads from master cylinder 204 to typical drum brakes 212. Upon activation of vehicle braking system 200, drum brakes 212 operate in a typical fashion to stop the rotation of rear wheels 213. Generally, when a user depresses brake pedal 202, cylinder 204 transmits the force hydraulically through the fluid lines, and the brakes transmit the force to the tires using friction to stop rotation of the tires. For illustration purposes only, vehicle braking system 200 is shown with disc brakes associated with the front wheels and drum brakes associated with the rear wheels. It should be appreciated that the types of brakes used with vehicle braking system 200 could be any number of a variety of brakes used with the front and rear wheels.

In certain embodiments, vehicle braking system 200 further includes a typical emergency braking subsystem 214 having an emergency brake handle 215. In the illustrated embodiment, emergency brake handle 215 can be engaged by a user to apply the emergency braking subsystem to rear wheels 213. As with system 200, the illustrated subsystem 214 is only one example of numerous possible configurations of an emergency braking system.

Sensing activation of the vehicle braking system occurs at step 108 (Fig. 20) In certain embodiments, sensing application of the vehicle brakes involves the use of an actuator or sensor associated with the vehicle braking system to send a signal when the vehicle brakes are applied. It is contemplated that the sensor could be incorporated into the vehicle braking system at a number of different locations. With reference to vehicle braking system 200, the sensor or actuator could be

associated with brake pedal 202, master cylinder 204, hydraulic lines 206 and/or 210, disc brakes 208 and/or drum brakes 212. Additionally, in certain embodiments, another actuator or sensor could be associated with emergency braking subsystem 214 to detect application of the emergency brake. As even
5 further examples, the sensor or actuator could be associated with the smaller pistons (not shown) or the brake pads/shoes (not shown) used in connection with the disc and drum brakes.

In other embodiments, the sensor may be an optical sensor used to detect movement of a component of the vehicle braking system. As an example, an
10 optical sensor may be used to detect movement of the brake pedal, such as brake pedal 202, to detect application of the vehicle brakes. In even other embodiments, the sensor may be associated with the brake lighting system of the vehicle, such that activation of the brake lighting system indicates application of the vehicle brakes. In yet other embodiments, the sensor may be a mechanical linkage component to
15 detect application of the vehicle brakes. In yet other embodiments, brake sensors may include temperature sensors (of brakes, brake fluid, rotor, drum, pads or otherwise), or may include a vehicle accelerometer (or decellerometer) connected to the controller, whether such controller is part of a general vehicle microprocessor and/or a stand alone controller for the seating system. In such embodiments, the
20 sensor may be engaged with the brake pedal, such that when a user depresses the brake pedal, the mechanical component activates a mechanical linkage system to suspend movement of the actuators. In another version, the sensor may be a computer software algorithm that senses any state in the vehicle's microprocessor(s) that corresponding with braking or deceleration. Such status in the
25 microprocessor(s) may be initiated by one or more of the above-mentioned sensors, as well as vehicle velocity, deceleration, or the like.

In certain embodiments, a sensor or actuator, examples of which are described above, sends a signal at step 110 in response to activation of the vehicle braking system. It is contemplated that the signal could be sent in numerous
30 possible ways. As an example, the signal may be an electrical signal sent from the sensor to an electrical unit which communicates with the actuators. In the example given above in which the sensor is a mechanical component, the signal could be

sent via mechanical linkage to suspend movement of the actuators. In such embodiments, the mechanical linkage may be configured to contact a power switch to turn the actuators off. As yet another example, the signal may be sent from the sensor to a controller via a hydraulic pressure mechanism.

- 5 In typical embodiments, the signal travels along an electrical line (or by radio frequency) to an electrical controller operable to activate and suspend movement of the seat adjustment actuators. The electrical controller may be integrated into the vehicle's electrical system. In certain embodiments, the electrical controller discussed herein is the central electrical unit of the vehicle.
- 10 Alternatively, the electrical controller may be an electrical unit designed specifically for activating and controlling the seat adjustment actuators. In certain other embodiments, the signal travels to specific seat adjustment actuators to suspend movement of the actuators.

 Fig. 2A illustrates an embodiment of the present system in which vehicular
15 seat 22 includes various seat adjustment actuators. The illustrated actuators A1 – A5 may be automatically activated by electrical controller C to alter the seating position formed by seat 22 to reduce user positional fatigue, as will be explained in greater detail below. Additionally, Fig. 2A illustrates brake pedal 202, adjacent a gas pedal 203, to activate vehicle braking system 200 (see Fig. 2B). In the
20 illustrated embodiment, a sensor 250 is positioned on brake pedal 202 and designed to produce an electrical signal in response to a user depressing brake pedal 203 to decelerate the vehicle. In such embodiments, the electrical signal travels along electrical line 252 to electrical controller C to suspend movement of the actuators during the critical event of braking. It should be appreciated that the
25 example shown in Fig. 2A is merely one example of many different possible configurations for sending a signal in connection with step 110 (Fig. 20).

 Fig. 1B illustrates components of a vehicle seating system 30 designed to reduce user positional fatigue. It should be appreciated that the system can be associated with any type of vehicular seat. System 30 includes various powered
30 seat adjustment actuators configured to move seat back 26 and seat bottom 28 in various manners, thereby altering the seating position formed by the seat. Certain typical embodiments include five actuators, such as a first actuator A1 to move

both the seat back and the seat bottom in a generally vertical direction along a height axis H and a second actuator A2 to move both the seat back and the seat bottom in a generally horizontal direction along distance axis D. Movement along the distance axis D alters the distance that the seat is positioned relative to a steering wheel and pedal system for a driver's seat. A third actuator A3 is configured to move a lumbar region of the seat back along a lumbar axis L. A fourth actuator A4 and a fifth actuator A5 operate to incline or tilt the seat back along an I axis and the seat bottom along a T axis, respectively. The actuator power may be by motor, servo motor, stepper motor, pneumatics, hydraulics, or otherwise.

In certain embodiments, movement of the actuators includes a slow movement average of less than about 15 centimeters per second. In some embodiments, movement may be at a slow movement average of less than about 10 centimeters per second. In certain embodiments, each actuator moves from a first position to a second position, and cycling of the actuators includes movement from the first positions to the second positions and returning to the first positions. In some embodiments, the actuators occupy third and consecutive positions before returning to the first positions. In certain embodiments, the first position of each actuator is a base position and the second position of each actuator is the opposite, completely extended position of each actuator along the respective axis. However, in certain other embodiments, the first position of each actuator is a desired position, predetermined by the system or a user of the system.

System 30 generally includes an electrical controller C to automatically activate, operate, and cycle through the various actuators in a manner as to reduce positional fatigue. The electrical controller may operate in conjunction with a microprocessor and/or computer chip technology to operate the system. Additionally, the electrical controller may operate in conjunction with software technology to control automatic movement of the actuators. The electrical controller may include a control period. In certain embodiments, a user of the system may trigger a control mechanism to initiate the control period (and thus initiate automatic movement of the actuators) at a time desired by the user. In certain other embodiments, the electrical controller initiates the control period

when the vehicle is turned on. In such cases, the control period may optionally include a first stationary time period before movement begins. In yet other embodiments, the electrical controller initiates the control period after passage of a first stationary time period beginning when the vehicle is turned on. In certain preferred embodiments, the first stationary period is about 20 minutes. In other preferred embodiments, the first stationary period is about 30 minutes. Further, it is contemplated that the control period can begin at other appropriate times as would generally occur to one skilled in the art.

In certain embodiments, the control period includes at least one fatigue period of at least ten minutes. In a preferred embodiment, the fatigue period includes at least one segment of time in which at least one actuator is moving to reposition the vehicle seat. In certain embodiments, the control period includes at least one movement period, including movement of at least one actuator, and optionally may include at least one stationary period in which the actuators are motionless. In certain embodiments, the stationary period is at least 5 minutes in duration. In certain embodiments, the control period ends when the vehicle is turned off.

As stated above, the electrical controller may be the central electrical unit of the vehicle's electrical system. In such situations, the electrical controller may be turned on when the vehicle is turned on, with a user of the system separately activating the controlling software, to initiate automatic movement of the actuators at a time desired by the user, by triggering a control mechanism linked with the electrical controller and the software. As an example, the control mechanism may include a button positioned on the vehicle's steering wheel or dash board area so that a user may activate and de-activate the automatic movement as desired. In other embodiments, the electrical controller may be a separate electrical component from the vehicle's central electrical unit, although electrically integrated into the vehicle's electrical system. In such cases, the electrical controller may be activated automatically when the vehicle is turned on and/or may be manually activated and de-activated by a user of the system. In the latter situation, a user of the system may manually switch the electrical controller on and

off as desired. Additionally, in certain embodiments, the electrical controller is deactivated when the vehicle is turned off.

Fig. 1C illustrates an alternative embodiment in which one actuating means AA, such as one power cylinder, is used to move the seat back and seat bottom to various seating positions through the use of various mechanical linkages such as bell cranks, worm gears, cams, etc. The actuating means AA and the mechanical linkages can be configured to cause movement at different actuating points, such as actuating points 40, 41, and 42, through the use of one actuating means. In other words, there may be one actuating means and more than one actuator at points 40, 41, and 42, for example. It is possible to link the actuators, as shown in Fig. 1C; however, it is often typical that the actuators operate independent of each other, as in Fig. 1B.

Referring to Fig. 1D, components of a seating system 130, similar in design and function to system 30, are illustrated. System 130 is designed to also help with one or more of the following: reduce user positional fatigue, reduce the effects of ischemia experienced by a user of the system during long distance traveling, and provide comfort to a user of the system. It should be appreciated that the system can be associated with any type of seat, including vehicular seat 22 as an example. System 130 can include various members, including powered seat position-adjustment actuators configured to move seat back 26 and seat bottom 28 in various manners, thereby altering the seating position formed by the seat. In certain embodiments, system 130 can include one or more of the position-adjustment actuators described in conjunction with system 30, including actuators A1 through A5. As described above, actuator A1 can move the seat along height axis H, actuator A2 can move the seat along distance axis D, actuator A3 can provide lumbar movement along lumbar axis L, actuator A4 can tilt the seat back along axis I and actuator A5 can tilt the seat bottom along axis T.

Additionally, the members of system 130 can include one or more thermal energizers configured to adjust the seating temperature of the seat and impact the circulation of a user of the system. As examples, system 130 can include a heating energizer E6 configured to provide heat to the seat and a cooling energizer E7 configured to provide a cooling effect to the seat. Further, in addition to position-

adjustment actuators, such as actuators A1 through A5, system 130 can include other mechanical energizers, such as a massaging energizer E8 configured to provide a provide a massaging effect to the seat. As another example, systems 30 and /or 130 can include a seat-extending member which extends the seat
5 underneath a user's thighs. It is contemplated that other members could be part of system 130 and/or system 30.

As described above, movement of the position-adjustment actuators A1 through A5 preferably includes a slow movement average of less than about 15 centimeters per second, and in some cases, less than about 10 centimeters per
10 second. Additionally, in certain embodiments, each actuator A1 through A5 and energizer E6 through E8 transitions from a first status to a second status, and cycling of the energizer members includes transitioning from the first statuses to the second statuses and returning to the first statuses. In certain embodiments, the first status of each position-adjustment actuator A1 through A5 is a base position
15 and the second status of each position-adjustment actuator is the opposite, completely extended position of each actuator A1 through A5 along the respective axis. Additionally, in certain embodiments, the first status of each energizer E6 through E8 is the standard "off" setting, and the second status is the standard "on" setting. However, in certain other embodiments, the first status of each energizer
20 member is a desired setting or position, predetermined by the system or a user of the system.

Similar to system 30, system 130 generally includes electrical controller C to automatically activate, operate, and/or cycle through the various energizer members in a manner as to reduce positional fatigue, impact a user's circulation,
25 and reduce the effects of ischemia. The electrical controller C may operate as described above in connection with system 30, including having a control period with stationary or hold periods, and movement or activation periods. In certain embodiments, massaging energizer E8 may include the use and operation of electronically controlled massage therapy systems. As an example, energizer E8
30 can include inflatable and deflatable gas or fluid chambers operable to provide a massaging effect through the seat back of the vehicle seat. In certain embodiments, energizer E8 can provide a vibratory massaging effect.

Additionally, in certain embodiments, energizer E8 can provide a rolling massaging effect traveling up and down the seat back of the vehicle seat, such as through the use of a rolling cam. Regarding the thermal energizers, heating and cooling energizers E6 and E7 may include the use and operation of conductive fluid to provide the desired thermal effect. Additionally, heating energizer E6 may include the user and operation of one or more electrical elements to provide heat to the vehicle seat.

Optionally, the actuators may cause movement at two or more speeds. For example, the actuators may cause movement at a first, lower speed for purposes of reducing or preventing fatigue, and have a second, higher speed for the user to adjust the position of the seat manually or through known seat memory position features. This allows for the seat to be changed to the preferred (typically starting) seat position relatively quickly. Such multi-speed actuators may come in a variety of forms. For example, they could include conventional brushless electrical motors, other electrical motors which are multi-speed (e.g., with two speeds, three speeds, or more speeds), and such multi-speed motors could include stepper motors and/or servo motors previously discussed. The controller would send a control signal to the motor (or other actuator) to use the higher speed, such as one button or other control, to manually or memory adjust the seat as activated, and send a signal for a slower motion for seat movement in connection with the anti-fatigue function. Such slower motion has the benefit of being less discernable by the driver and/or less likely to surprise or startle a driver during its operation. Alternatively, such optional multi-speed actuators may also include multi-speed hydraulic and/or pneumatic actuators as previously discussed, with the rate of movement preferably controlled by valving and/or inflation/deflation rates.

Referring to Figs. 3A-5, various examples of optional movement profiles are illustrated. These are merely samples, and numerous others are possible as well. They depict time on the horizontal axis (or x-axis) and movement amplitude on the vertical axis (or y-axis). For example, these Figs. 3A-5, which are drawn to scale, depict examples showing minutes, including decimal fractions of minutes. For example, 0.33 minutes equals 20 seconds. The displacement may be in terms of length (linear and/or curvilinear or otherwise) and/or in terms of angular

displacement, measured in terms of angles, stepper or servo motor position, or otherwise. Displacement is synonymous with amplitude, and amplitude need not be cyclical. For purposes of illustration, such displacement is depicted as having positive and negative numbers, thereby denoting that dead center is at a zero (“0”) displacement value. Of course, this could be expressed as all positive numbers, all negative numbers, or otherwise.

Fig. 3A depicts movement profiles of actuator 1 (3A1) and actuator 2 (3A2) along a time axis and displacement axis. Such actuators may, be any of the actuators previously described, and/or may include more or less actuators. As illustrated, actuator 3A1 is shown as a series of steps depicted by horizontal stationary periods and upwardly sloping and/or downwardly sloping movement. In this particular example, for example, movement is depicted as cyclical from a peak of +3 to a peak of -3. Other profiles, cyclical or non-cyclical or both, may be used as well. Profile 3A2 of actuator 2 is shown as being more of a back and forth with longer and shorter stationary periods between the 0 position and the 1 position of displacement. For example, Fig. 3A may depict movement of actuator 3A1 corresponding to the inclining I of seat back 26 (see Fig. 1B, Fig. 1D, for example). Movement profile 3A2 may, correspond to lumbar movement L (see, for example, Fig. 1B and/or Fig. 1D). Of course, such actuators may correspond to seat bottom tilting T, and/or adjustment H and/or D, or otherwise.

Fig. 3B, in comparison and in contrast to Fig. 3A, shows a changing of the seat movement. For example, seat movement 3A1 of Fig. 3A may be altered to a different profile, depicted as profile as 3A3 shown in Fig. 3B. Similarly, by comparison, movement profile 3A2 (Fig. 3A) may be changed to movement profile 3A4 (Fig. 3B). Such changing may be in response to a vehicle/user event while the vehicle is moving (and/or in drive and thus typically moving). For example, with reference to Fig. 3B, there may be one or more vehicle/user event or triggering events depicted at TG. Such triggering events may be a single event, a combination of events, or a result or results of a computed outcome or value. For example, as illustrated in Fig. 3B, a series of spikes are illustrated on the trigger plot such as at 301. In the particular example, seven such trigger events are illustrated, although more or less and/or other trigger events may be utilized. In

such a case, upon sensing such vehicle-driver event, the controller C may alter the movement of the seat actuators and/or seat movement profiles. For example, as shown in Fig. 3B, this is shown as “city mode”, depicted therein as the binary status, namely either in city mode or not in city mode. For example, this may be expressed in terms of a highway mode or a city mode. However, the system is not limited to binary statuses, but may include 3, 4 or more statuses or modes and/or hybrid of modes. Moreover, they also may include a sliding scale or gradient transition or change of status, such as with coefficient indicating a degree of change (e.g. frequency and/or amplitude) and being multiplied by a frequency value, an amplitude value, both or otherwise. Also, a change of movement may be a change in actuator speed, and corresponding seat movement speed, which comprises both a change of frequency and amplitude for that time segment. Note that before city mode CT, the movement profiles are a first status corresponding to Fig. 3A, but during city mode CT, they move to a second movement profile. However, after the conclusion of city mode CT, they change to another mode, in this example reverting back to the original movement profiles 3A1 and 3A2, as shown in Fig. 3A. For example, in Fig. 3B, movement profile 3A3 shows a higher frequency movement, as depicted in the shorter duration stationary period 320, as compared to the longer duration stationary period 321. The longer stationary period 321 may, for example, correspond to a highway (or other) mode or status. Thus, for example, when the vehicle operating as depicted in Fig. 3B transitions from a highway mode to city mode CT, the average movement frequency increases, and after the city mode the movement profile changes to a lower frequency movement.

Fig. 4 illustrates several optional attributes that may be included, or not included, in connection with the features claimed. Fig. 4 likewise shows on the horizontal axis time, and a value figure on the vertical axis. Fig. 4 is expressed in terms of “intensity” which normally means speed, but may also be expressed in terms of force or displacement, or a combination thereof. Fig. 4 depicts actuator 1 intensity (4A), actuator 2 intensity (4B) and actuator 3 intensity (4C) plotted as a function of time. Note that actuator intensity 4A may be variable as a function of time. Actuator intensity 4B has a lower value, but is otherwise constant, and

actuator 4C is at a higher intensity value, but likewise is constant. With regard to variable actuator intensity, such as variable actuator speed, this optional feature may be utilized in connection with and/or in response to one or more inputs. For example, instead of or in addition to, or along with, frequency variations of movement profile be a function of stationary time, they also may be a function of actuator speed. Thus, for example, transitioning to or from highway mode and/or city mode, or other modes, actuator intensity may be adjusted in response to various vehicle/user events described elsewhere. Another feature, not unique to the present system as a stand alone feature, but nevertheless optionally includable, is a shake-to-wake feature in which actuators are used to vibrate or jolt or alert a driver if the system senses fatigue, such as a driver dozing off. Such fatigue indication F (see Fig. 4) is depicted as spikes corresponding to sense fatigue input, as is known elsewhere, such as discerning eye movement patterns, drifting off the road, speed fluctuations, time of day and/or driving conditions (e.g., late night) that give an indication, or at least a probabilistic indication, of driver fatigue and/or dozing off. In such case, in addition to the long term fatigue reduction of the present invention, such prior art shake-to-wake features may optionally be included in combination with some or all of the claimed features of the present system. They may trigger shaking via actuators and/or audible and/or visual alarms.

Optionally, actuator speed may be altered mid-move as being a change of frequency and amplitude (at least for that movement segment) as previously discussed. Moreover, optionally actuator speed may be higher at first, such as a burst of power to a motor to get it moving (or to get it unstuck) followed by the motor moving at a slower speed(s).

Figs. 5A-5E illustrate merely examples of possible movement profiles. For comparative illustration, the profile in Fig. 5A can be thought of as the starting point, default, or baseline profile, with the other profiles being variations thereof. However, the other profiles may be considered such default profiles as well (see for example, Figs. 6-18). By way of examples, Figs. 5A-5E show the time along the x-axis depicted in minutes, including fractions of minutes. They may be expressed in seconds or otherwise. This is drawn to scale, although optionally other time intervals may be used as well. Likewise, the y axis the movement

displacement is shown in relative values, positive and negative. Fig. 5A depicts a generally cyclical, approximately sinusoidal, cycle pattern for movement about the “Y=0” axis. It is shown as a stair step, although it may be rounded curves or multiple slopes as well. Movement profile 7A is illustrated with series of stationary periods. For examples, stationary periods 780a, 780b, 780c, 780d, 780e, 780f, 780g, 780h, 780i, 780j, 780k and 780l are illustrated. Example positions are illustrated, such as position 750 and position 751. For example, position 750 is shown at the positive peak displacement (+3), and the average movement frequencies are the time between the first position 750 through one or more second positions displaced from 750, (e.g., between 750 and position 751) and back to first position as 751. In other words, the movement from position 750 to 751 cycles through positive and negative displacement locations over a period of time with position 751 be in the same position as 750 albeit at a later time. The average movement frequency is the period of time (distance on the horizontal x axis) between position 750 and 751. However, note that such time between first position to a second position and back to the first position need not necessarily be at a peak or apex of a movement cycle. For example, this time value also may be measured by comparing position 752 to position 752A, and again to position 753 in Fig. 5A. In all three such positions, the displacement of the given actuator is at the same position (namely, a value of negative 1 in Fig. 5A). However, the time between such positions is shorter as between position 752 and 752A than it is between position 752A and 753. However, the average movement frequency would, in this example, average the lesser time (752 to 752A) and the greater time period (752A to 753). Thus, by comparing Fig. 5A with Fig. 5B, one example of changing the actuator, and hence seat portion movement, is changed. Fig. 5B is substantially the same as Fig. 5A except that the cyclical motion happens at a higher frequency. Thus, position 1750 and position 1751 are closer together in terms of time, reflecting a higher frequency. Likewise, position 1752, 1752a, and 1753 are closer together than their counterparts (752, 752A, and 753 in Fig. 5A) both individually and by averaging both values. Thus for example, the controller may be adapted for receiving at least one signal based on at least one vehicle/user event while the vehicle is moving, and changing the seat actuator movement (and hence the

corresponding seat back, seat bottom, lumbar support, seat height, etc.) movement from the first average movement frequency 7A (Fig. 5A) to a second higher average movement frequency 7B (Fig. 5B) based at least in part on the signal. Such signal may be one or more of combination discussed elsewhere, including but not limited to transitioning from highway driving to slower, non-highway driving. Other examples may be used as well. These could include (a) night driving vs. day driving; (b) relatively straight driving vs. numerous turns; (c) level driving vs. uphill/downhill driving; (d) sleepy vs. non-sleepy; (e) driver identity, combination(s) thereof, and/or otherwise.

10 Comparing Fig. 5C to Fig. 5A (and/or to Fig. 5B) it can be seen that rather than altering the frequency, the average frequency remains the same, but the amplitude of movement has been reduced by some amount. In the illustrated embodiment, drawn to scale, Fig. 5C's amplitude is reduced by a coefficient of 2/3 (or 0.666). Thus, for example the peak positive displacement in Fig. 5C is 2, 15 whereas the peak positive displacement in Fig. 5A is 3 in relative terms. Thus, the vertical distance between location 2750 and location 2752 is reduced as compared to location 750 and location 752. The average frequency in this illustrated embodiment of Fig. 5C between 2750 and location 2752, as well as between location 2752 and location 2751, as compared to the corresponding 20 locations (750, 752 and 751) in Fig. 5A is the same in this example. Thus, as with Fig. 5B, rather than altering the frequency, one may change the amplitude. Of course, the current system can be set up to do one or both, increase and/or decrease frequency and/or increase and/or decrease amplitude, alone or together.

Fig. 5D illustrates actuator/seat movement profiles 7D1 followed by profile 25 7D2. The transition from profile 7D1 to profile 7D2 is caused or triggered by one or more vehicle/user events, such as events 701, 702 and/or 703. These may, for example, happen within a predetermined time period P. Under this one example, once three such events occur within time period P, the controller, sensing this, sends a control signal during second mode depicted as shading at mode 700D. 30 During such second mode, the actuator movement is changed. In this particular depicted example, the amplitude increases and the frequency increases as illustrated. For example, a stationary period 781f is lesser or shorter than

stationary period 780e. The second mode 700d continues until some predetermined time and/or until one or more predetermined vehicle/user event(s) or combination thereof, as illustrated in Fig. 5D.

Fig. 5E illustrates another variation profile 7A (discussed in connection with Fig. 5A). As shown in Fig. 5E, a single vehicle/user event 704 may, optionally, cause a suspended mode 701. The suspended mode is an optional feature, and corresponds with a lack of change of motion depicted at regions 7E1. This feature is described further elsewhere including in connection with 106, 108, 110, 112 and 114 in Fig. 20. Additionally and/or instead of this, the vehicle system may go into a second mode 700E, changing the profile at 7E2 as illustrated. In such mode, the frequency may be the same or changed, and as illustrated the amplitude is reduced such as for example, as discussed in connection with the examples of Figs. 5A-5D.

One optional set of seat movements can be as follows. The seat back 26 incline movement I is back and forth, generally cyclical with stationary periods. For example, the seat back may move incline I between -3° to $+3^\circ$, with negative being back and positive being forward from a starting 0° position. The seat bottom 28 may be different. When the seat back 26 is in a position forward ($+3^\circ$) of where it started, the seat bottom moves between 0° and $+1^\circ$, (with positive being up tilt T). This may be done while the seat back 26 is stationary or moving. As one example, while seat back 26 is moving, in the time the seat back takes to move from 0° to $+3^\circ$ to 0° , the seat pan has moved from 0° to $+1^\circ$ back to 0° three times, when the angular speeds are the same. And, in this example, once the seat back is moved behind its starting point towards -3° , the seat bottom oscillates between 0° and -1° (down), again three times per the seat back's single cycle. Of course, these ratios may optionally be otherwise, and this is merely an example of relative movement of the seat back and the seat bottom. Likewise, the values of 3 degrees and 1 degree as set forth and the values may be greater and/or lesser.

It is to be understood that Figs. 5A-5E, like the other figures, are merely examples, they may be curvilinear, have various slopes and lengths, and other shapes. Moreover, for drawing simplicity they only depict the movement of a single actuator and/or seat portion moved by that actuator. However, it is to be

understood that one more such profiles may be overlaid with each other in synchronization or counter motion or otherwise. Examples of such overlay of multiple actuators and multiple profiles include those set forth in drawing Figs. 6-16, discussed further below. Thus, for example, the profiling transitions of Fig. 5D
5 may be applicable to a seat back, whereas a profiling motions of Fig. 5E may be applicable to an actuator for a seat bottom, or vice versa. The same is true with the other drawing figures and are merely non-limiting examples.

The following Figs. 6-16 as well as Figs. 17 and 18 are merely further examples of possible baseline or first movement profiles, with being understood
10 that such movement profiles may be changed, either in binary form, transitory or otherwise, as previously described in connection with Figs. 3A-6B.

Figs. 6-16 are graphic illustrations of various embodiments of a vehicle seating system to adjust the position of the vehicle seat. The figures further

illustrate movement of various actuators along a horizontal Time axis and a vertical Movement axis. The Movement axes generally include a "1" denoting a first position and a "2" denoting a second position, and certain figures include delineations along the Movement axes denoting partial movement between the first and second positions. It should be appreciated that the first and second positions can be various combinations of actuators and activation position levels thereof, and can be randomly chosen or predetermined by the system or a user of the system. They could be full stroke or partial stroke (or rotation) of the actuators. In certain embodiments, the transition time for the actuators to move from the first positions to the second positions is in the range of 20 – 40 seconds.

Figs. 6-16 represent only a few of numerous embodiments of actuator movement profiles of a vehicle seating system as described herein. In the illustrated embodiments, optionally a first time period passes before movement on Movement Axis M between positions 1 and 2 of one or more actuators begins. In certain embodiments, the initial movement of one or more actuators is the beginning of the control period. In certain other embodiments, the control period includes an initial period of time of inaction of the actuators. In other words, in certain embodiments the Time axis T begins with the vehicle turning on, and in certain other embodiments, the Time axis T begins with the beginning of the control period. Further, the illustrated embodiments are not meant to be limiting in any manner, including regarding the number of actuators illustrated in the figures. It should be appreciated that the embodiments illustrated in the figures can include movement of a different number of actuators as would occur to one skilled in the art. Also, although the movement profiles illustrated in Figs. 6-16 are linear segments, they may optionally include curvilinear segments as well. In certain embodiments, the actuators move with a slow movement speed average of less than about 15 centimeters per second. In some embodiments, the actuators move with a slow movement speed average of less than about 10 centimeters per second, and may be an average of less than about 2 centimeters per second. Additionally, it should be appreciated that the activity of the actuators illustrated in the figures can continue indefinitely along the Time axis, with only a segment of the activity

shown for clarity. Also, any and all of the profiles in Figs. 6-16 and otherwise may be combined with each other.

The control period may include one continuous movement period, wherein at least one actuator is moving through different seating positions. Two such
5 actuators may move continuously; however, it should be appreciated that a different number of actuators can reposition the seat during the movement period. The movement period may include cycling of the various actuators from first
10 positions to second positions continually until the control period ends.

Fig. 6 is a graphic illustration of another possible embodiment of a vehicle
10 seating system. In the embodiment illustrated in Fig. 6, the control period includes a movement period followed by a stationary period of inaction of the actuators. It should be appreciated that this movement period and stationary period alternating combination can continue along the Time axis. The illustrated movement period includes cycling of the actuators from respective first positions to second positions,
15 and returning to the first positions. The embodiment illustrated in Fig. 6 includes relatively slow cycling of the actuators to reduce positional fatigue of a user without significant disruption to the user.

In the embodiment illustrated in Fig. 7, the control period includes alternating movement periods and stationary periods. In certain preferred
20 embodiments, each movement period includes cycling of the actuators from first positions to second positions and returning to first positions. In such embodiments, each stationary period includes static positioning of the actuators at the first positions. However, it should be appreciated that, in certain alternative embodiments, a movement period can include movement of the actuators from first
25 positions to second positions, and a next consecutive movement period can include movement of the actuators from second positions to first positions, with such a continuing alternating pattern. Additionally, in certain alternative embodiments, the movement periods can include other segments of the cycling from first
30 positions to second positions, with stationary periods occurring therebetween.

Fig. 8 is a graphic illustration of yet another possible embodiment of a
vehicle seating system. In the embodiment illustrated in Fig. 8, the movement is similar to that in Fig. 7, except that there are additional stationary periods

occurring after some of the movement segments and before returning to the original position "1" as illustrated.

Fig. 9 is a graphic illustration of yet another possible embodiment of a vehicle seating system. In the embodiment illustrated in Fig. 9, the control period
5 includes alternating movement periods and stationary periods. In certain embodiments, each movement period includes slight movement of at least one actuator along a segment of the distance between the first and second positions. The movement periods begin with the at least one actuator moving from a first position toward a second position, reaching the second position and then returning
10 toward a first position, with stationary periods occurring throughout. In certain embodiments, the stationary periods are longer in duration than the movement periods, as illustrated. In the illustrated embodiment, the movement periods include movement equivalent to a quarter segment of the distance between the first and second positions. However, it should be appreciated that the movement
15 periods can include different length segments as would occur to one skilled in the art, including different lengths than the illustrated embodiment and/or different lengths within the same control period for different movement periods. It is also contemplated that movement of one or more other actuators occurs when the illustrated actuators are stationary. In such cases, one or more actuators move and
20 then are stationary, and then one or more other actuators move while the first set of actuators are stationary.

In the embodiment illustrated in Fig. 10, the control period includes one continuous movement period, wherein the actuators are moving through different seating positions, with one actuator moving before another. Fig. 10 illustrates two
25 such actuators; however, it should be appreciated that a different number of actuators can reposition the seat during the movement period. The movement period illustrated in Fig. 10 includes cycling of the various actuators from first positions to second positions continually until the control period ends. In some embodiments, the actuators move such that certain actuators reach first positions
30 when various other actuators reach second positions, and vice versa. In certain embodiments, the movement period illustrated in Fig. 10 includes movement of at least two seat adjustment actuators.

Fig. 11 is a graphic illustration of even another possible embodiment of a vehicle seating system. The control period illustrated in Fig. 11 includes one continuous movement period, wherein the actuators are moving simultaneously through different seating positions. In certain embodiments, the five actuators
5 illustrated in Fig. 11 are the five actuators described in connection with Fig. 1B. The movement period illustrated in Fig. 11 includes cycling of the various actuators from first positions to second positions, and back to first positions, continually until the control period ends and with a relatively slow movement average.

10 In the embodiment illustrated in Fig. 12, the control period includes various combinations of movement periods and stationary periods, wherein the actuators are moving through different seating positions. The movement period illustrated in Fig. 12 includes cycling of the various actuators from first positions to second positions, with some actuators having stationary periods at certain positions. Fig.
15 12 is illustrative of the possibility of the various actuators being activated to move at different speeds, and with different combinations of movement periods and stationary periods. Additionally, in certain embodiments, a user can preprogram various desired seating positions to be cycled through. It is contemplated that a user may set each actuator to a desired position, with the actuators collectively
20 defining a preprogrammed seating position. In other embodiments, the seating positions are chosen at random by the system.

Fig. 12 illustrates times T1 through T8. In certain embodiments, the vehicle is turned on at time T1, with electrical controller C being activated and initiating a control period at time T1. In the illustrated embodiment, a first
25 stationary period occurs from time T1 to time T2, in which the actuators remain motionless at position 1, and movement periods begin at time T2. During the movement periods, the actuators cycle at various speeds and through various positions. In the illustrated embodiment, for example, actuator 1 cycles continuously through a single movement period from time T2 to T8, while actuator
30 5 includes alternating movement periods and stationary periods. Additionally, as a possible example, from time T2 to time T3, actuator 1 cycles from position 1 to position 2 and back to position 1, while actuator 5 cycles from position 1 to

position 2 relatively quickly and then remains at position 2 through time T3. Actuator 5 then returns relatively quickly to position 1 at time T4, with this pattern continuing through the movement periods and stationary periods. However, it should be appreciated that other patterns can be implemented for the actuators as would occur to one skilled in the art and/or as desired by a user of the system. Additionally, it should be appreciated that the various movement patterns of the actuators can be randomly chosen by the vehicle seating system or can be pre-programmed by a user of the system. For brevity, the discussion of a control period including times T1 through T8, and the examples discussed herein, have been provided in conjunction with Fig. 12, but similarly apply to Figs. 6-16.

Fig. 13 is a graphic illustration of another possible embodiment of a vehicle seating system. The control period illustrated in Fig. 13 includes movement periods in which only one actuator is cycling through seating positions at a time. In certain embodiments, a first actuator cycles from a first position to a second position and back to a first position, with other actuators then following the same pattern. In such embodiments, each actuator includes periods of inactivity, with the overall control period including one continuous movement period with only one actuator cycling at a time.

In the embodiment illustrated in Fig. 14, the control period includes alternating movement periods and stationary periods. The movement periods include movement of the actuators to specified predetermined positions, with stationary periods occurring therebetween. In certain preferred embodiments, a user of the system pre-selects one or more seating positions using a combination of positions of the actuators. In such embodiments, the movement periods cycle the actuators to the pre-selected seating positions with a slow movement average over the control period.

Fig. 15 is a graphic illustration of even another possible embodiment of a vehicle seating system. In the embodiment of Fig. 15, the control period includes alternating movement periods and stationary periods with reference to different actuators. Initially, actuators 2 and 3 are stationary at respective home positions while actuator 1 alternates between movement and stationary periods to slowly transition from a first position to a second position and back to the first position.

Upon returning to the first position, actuator 1 remains stationary at the first position while actuators 2 and 3 transition to respective second positions.

Thereafter, actuators 2 and 3 remain stationary at the respective second positions while actuator 1 again slowly transitions from a first position to a second position and back to the first position via alternating movement periods and stationary periods. Upon returning to the first position, actuator 1 remains stationary at the first position while actuators 2 and 3 transition from the respective second positions back to the respective home positions. In such embodiments, the actuators may continue such cycling pattern indefinitely.

Fig. 16 is a graphic illustration of a further possible embodiment of a vehicle seating system. The illustrated embodiment in Fig. 16 includes an initial movement spike of actuators 1 and 2 from a first position to a second position, followed by alternating movement and stationary periods to return the actuators from the second position to the first position. In such embodiments, the initial movement spike includes increased relative movement of the actuators as compared to movement within the subsequent movement periods. As with the other embodiments, the first and second positions may be random, predetermined and/or pre-selected by a user as desired.

Additional embodiments of a vehicle seating system include a typical vehicle seat mountable in a vehicle, at least two powered seat adjustment actuators, such as energizer members including at least one thermal energizer to adjust the temperature of the seat, and an electrical controller. The energizer members may also include mechanical energizers, such as a massaging energizer, a thigh or seat-extending actuator and/or seat position actuators as described above. The energizer members are optionally able to transition between various settings in conjunction with the seat to provide comfort to a user of the system and impact the user's circulation, thereby reducing positional fatigue experienced by the user. The electrical controller may have a control period which generally includes at least one activation period and, in certain embodiments, at least one stationary or hold period. In a typical embodiment, the electrical controller initiates the control period after a first time period beginning when the vehicle is turned on. Thereafter, the control period may include at least one activation period where the

energizer members automatically cycle through seating conditions to impact the user's circulation and reduce long distance traveling fatigue.

Figs. 17-18 are graphic illustrations of various embodiments of a vehicle seating system. Similar to Figs. 6-16, Figs. 17-18 illustrate movement or
5 activation of various energizer members along a horizontal Time axis and a vertical Activation axis. The Activation axes generally include a "1" denoting a first status and a "2" denoting a second status, and certain figures include delineations along the Activation axes denoting partial movement of the position-
10 adjustment actuators between the first and second statuses. It should be appreciated that the first and second statuses can be various combinations of energizer members, and activation levels thereof, and can be randomly chosen or predetermined by the system or a user of the system. In certain embodiments, regarding energizers E6 through E8, the first situation "1" represents the particular energizer in the "off" position and the second situation "2" represents the particular
15 energizer in the "on" position.

Figs. 17-18 represent only two of the numerous possible embodiments of condition profiles of a vehicle seating system, such as system 130. In the illustrated embodiments, optionally a first time period passes before activation on
20 Activation axis A of one or more energizer members begins. In certain embodiments, the initial activation of energizer members is the beginning of the control period. In certain other embodiments, the control period includes an initial period of time of inactivation of the energizer members. In other words, in certain embodiments the Time axis T begins with the vehicle turning on, and in certain other embodiments, the Time axis T begins with the beginning of the control
25 period. Further, the illustrated embodiments are not meant to be limiting in any manner, including regarding the number of energizer members illustrated in the figures. It should be appreciated that the embodiments illustrated in the figures can include activation of a different number of energizer members. Also, although the condition profiles illustrated in Figs. 17-18 are linear segments, they may
30 optionally include curvilinear segments as well. It should be appreciated that the activity of the energizer members illustrated in the figures can continue indefinitely along the Time axis T, with only a segment of the activity shown for clarity. Also,

any and all of the profiles in Figs. 6-16 and 17-18 may be combined with each other.

Fig. 17 is a graphic illustration of a possible embodiment of a vehicle seating system, such as system 130 for example. The control period illustrated in Fig. 17 includes activation periods in which only one energizer member is initiated to transition through seating conditions at a time. In certain embodiments, a first energizer member transitions from a first status to a second status and back to a first status, with other energizer members then following the same pattern. In such embodiments, each energizer member includes periods of inactivity, with each activation period including only one energizer member transitioning at a time. In the embodiment illustrated in Fig. 17, heating energizer E6 initially transitions to the second status "2" for a certain amount of time, representing that the heating energizer is turned on, with the heating energizer E6 then transitioning back to the first status "1", representing that the heating energizer is turned off. According to the illustrated embodiment, following the activation of heating energizer E6, massaging energizer E8 follows a similar pattern and then cooling energizer E7 follows a similar pattern. A hold period follows activation of the cooling energizer E7, with the pattern continuing again after the hold period.

Fig. 18 illustrates another graphic illustration of a possible embodiment of a vehicle seating system, such as system 130 for example. In the embodiment illustrated in Fig. 18, the control period includes an activation period with one or more energizer members remaining at the second status while one or more other energizer members are slowly transitioning between the first and second statuses. In certain embodiments, the control period begins when the vehicle is turned on, and thereafter includes a hold period before activation of energizer members is initiated. Additionally, in certain embodiments, each activation period includes slow movement of at least one position-adjustment actuator, such as lumbar actuator A3, between the first and second statuses, while at least one thermal energizer, such as heating energizer E6, continually remains at the second "on" status. It is contemplated that the activation and hold periods can be longer or shorter in time, than as illustrated in Fig. 14, as would generally occur to one skilled in the art.

During the activation periods of the illustrated embodiment, the energizer members cycle at various speeds and through various statuses. For example, heating energizer E6 may transition to the second "on" status, remain at the second status for a certain time period and then transition back to the first "off" status. At the same time, in the illustrated embodiment, lumbar actuator A3 may be activated and slowly transition from a first status to a second status, and back to a first status. In other embodiments, lumbar actuator A3 could transition at least twice between the first and second statuses during one activation period. However, it should be appreciated that other patterns can be implemented for the energizer members. Additionally, it should be appreciated that the various patterns of the energizer members can be predetermined routines, randomly chosen routines, and/or can be pre-programmed by a user of the system.

Fig. 19 illustrates a block diagram of a system 100, and particularly one example of optional steps. The vehicle turned on step 102 includes, at a minimum, turning on the engine, but more preferably also may include placing the vehicle transmission in drive. At some point, preferably during the control period, actuator movement 104, begins with one or more actuators as previously described. Such actuator movement is in a first average movement, typically ascertained in terms of frequency and/or amplitude, as described elsewhere. Vehicle/user events 104 cause a controller, which is adapted for receiving at least one signal based on such vehicle/user events, occurs at step 104B. While the vehicle is turned on, and preferably while the vehicle is moving, the step 104C of changing movement from a first movement to a second movement (and/or other movements), third movement, fourth movement . . . nth movement occurs to alter actuator movement 104. Examples of vehicle/user events are detailed further below. The vehicle/user event may include differentiating between highway driver and slower, non-highway driving, such as for example city driving. They may cause changes in an average movement frequencies that are the time between movements a corresponding actuator, and/or are the time between first movement position to a second movement position back to a first position. Preferably, but not necessarily, there is at least one stationary period of at least five minutes in duration in which a given power seat actuator are motionless while the vehicle is moving, and this optionally

is followed by actuator movement automatically after that stationary period. The changing actuator movement 104C also may include automatically adjusting movement amplitude of one or more of the powered actuators. As detailed further below, vehicle/user events 104A may include one or more values or inputs. In but
5 one example, these may include evaluation of one or more of elapsed time, speed and braking. For example, the controller may determine that an average speed is below 50 mph, and that in a elapsed time of five minutes, the brakes were tapped at least five times. Of course, these values may be changed. In such case, the controller may, in effect, be programmed to conclude the vehicle is in city mode,
10 and accordingly adjust the profile to a city mode profile of movement, more classically having more frequent movement as previously described. Of course, city movement may also have periods of lesser frequency of movement, changes in amplitude or otherwise.

Fig. 20 illustrates a block diagram of a system 100 with optional aspects,
15 the diagram showing various steps or stages of the system. Steps 102, 104, 104a, 104b, and 104c are as previously described. Initially, at step 102 the vehicle is turned on, namely the transmission is put in drive while the motor is running, by a vehicle user. Step 104 represents movement of one or more seat adjustment actuators to alter the seating position of the vehicle seat. In certain embodiments,
20 the actuators are activated manually by a vehicle user. In such cases, the user may activate the actuators, typically individually, as desired to provide comfort for the user. In certain other embodiments, the actuators are automatically activated by an electrical controller, which will be discussed in greater detail below with reference to Figs. 5A-19. In such cases, an optional step of triggering a control mechanism
25 which initiates the automatic movement of the actuators may be present between steps 102 and 104. The control mechanism may include a button accessible to the user and linked with software on the electrical controller which controls the automatic movement of the actuators. In alternative embodiments, the automatic activation may be initiated when the vehicle is turned on at step 102.

30 Step 106 represents a vehicle user activating the vehicle's braking system by at least partially depressing the brake pedal of the vehicle to decelerate the vehicle. Under the present system, this triggering event leads to suspending any

movement of the seat adjustment actuators. As an example, Fig. 2B shows a skeleton drawing of a typical vehicle braking system 200 using hydraulics, to better illustrate the operation of system 100. However, it should be appreciated that the present system may be used with many different vehicle braking systems, with system 200 only being one example of numerous possible configurations.

Movement of the actuators may be suspended at step 112 in response to application of the vehicle brakes, as discussed above. In typical embodiments, an electrical signal is sent to the electrical controller, as described above in connection with step 110, which directs the electrical controller to suspend movement of the actuators. However, other embodiments are contemplated, such as a mechanical linkage system or a hydraulic pressure system, as mentioned above, implemented to stop or redirect power sent to the actuators.

In accordance with the typical embodiment, electrical controller C may be encoded with logic executable to suspend movement of the actuators for a hibernation period upon receiving the electrical signal. In certain embodiments, the electrical controller suspends movement of the actuators during the time that the vehicle brakes are applied. The electrical controller may suspend movement of the actuators for an additional delay period after a vehicle user removes any foot pressure from the brake pedal. As an example, the delay period may be at least a few seconds, and normally at least 5, or sometimes at least 10 seconds after a user lets off the brake pedal. In a specific embodiment, the electrical controller suspends movement of the actuators during application of the vehicle brakes and for an additional delay period of about 15 seconds after the end of application of the vehicle brakes. The delay period may be longer or shorter. As another example, the delay period may be at least 1 minute after a user lets off the brake pedal. In even other embodiments, the electrical controller may suspend movement of the actuators until the user of the system reactivates the actuator movement. The vehicle seat occupies a temporary suspended position during the hibernation period corresponding to the positions of the actuators when movement is suspended. Following the suspension of movement, the actuators may be available for further independent movement by a user, or the electrical controller

may reactivate automatic movement of the actuators as discussed below in connection with optional step 114.

Optionally, the electrical controller may be encoded with logic executable to reactivate automatic movement of the seat adjustment actuators at step 114. In certain embodiments, the actuators are automatically activated to move in accordance with a predetermined routine, and may be suspended in response to a critical event such as vehicle braking, as described above. In such situations, the electrical controller may reactivate movement of the actuators following the critical event and continue with the same predetermined routine from the point where the routine was suspended. In other words, the vehicle seat may be said to have obtained a temporary suspended position when the suspension of movement of the actuators occurs, with the electrical controller being operable to reactivate movement of the actuators beginning from the temporary position. In one optional example, if the brake has been held for a period (e.g. over 10 seconds), the movement of the seats will resume; if the brake pedal is released mid-move, the then moving actuator will continue moving to its end point, but another actuator that follows will be paused a period of time (e.g. 5 seconds) before its movement. In certain other embodiments, the electrical controller may reactivate movement of the actuators following the critical event to return the seat to a base or home position. As described above, in certain embodiments the electrical controller may reactivate movement of the actuators following a delay period after a user lets off the brake pedal (and thus de-activates the vehicle braking system). In other embodiments, the electrical controller may reactivate movement of the actuators immediately after a user lets off the brake pedal, with the delay period being absent.

In alternative embodiments, the electrical controller may only reactivate movement of the actuators upon activation by a user of the system. Accordingly, the automatic movement of the actuators may be suspended until such time as a user of the system activates a triggering mechanism to re-start automatic movement of the actuators. Such embodiments may be associated with certain vehicle events such as air bag deployment. It is also contemplated that the system may provide for both automatic reactivation of the actuators as well as user re-

activation of the actuators depending on the type of critical event which the vehicle experiences. As an example, braking alone may trigger automatic reactivation by the electrical controller, while air bag deployment may trigger suspension of actuator movement requiring user re-activation.

5 Another system according to the present disclosure (not diagrammed for simplicity) contemplates the electrical controller being operable to take notice of the activation status of the vehicle braking system to determine if suspension of movement of the actuators is required. In such cases, the electrical controller may use electrical signals proactively to determine if the brake pedal is depressed and
10 accordingly suspend movement when necessary. In certain embodiments, the electrical controller may assess the activation status of the vehicle braking system before each predetermined routine begins and/or before each movement of an actuator within a predetermined routine. The system of proactively determining the activation status of the vehicle braking system can be implemented in addition
15 to system 100, such that the two systems work together to suspend movement of the actuators during critical events the vehicle may undergo. One optional example is that the system is suspended only if an actuator is moving or is set to move within a defined period (e.g. within the next 5 seconds), as opposed to suspending movement by the addition of a defined period (e.g. adding 5 seconds)
20 of non-movement to a movement profile of some or all actuators.

 As an alternative to and/or in addition to a signal sent in response to application of the vehicle brakes, or deployment of an air bag, the signal may be sent in response to one or more other vehicle/user events 104a. As examples, the event(s) 104a may be movement of the steering wheel (preferably beyond a pre-
25 determined amount and/or rate of turning), activation of a turn signal, activation of the hazard flashers, changing gears (including for example changing out of drive, changing to a lower or higher gear, changing to neutral, and/or changing to reverse), application of vehicle brakes (discussed above), rates (and/or change of rates) of accelerations and/or deceleration, activation of one or more air bags
30 (discussed above), activation of traction control, activation of anti-lock braking (ABS), a seatbelt not fastened, a seatbelt pre-tensioner activated, open door, high speed operation of the vehicle (e.g. higher than 70, 75, 80, 85, 90, 95 or 100 miles

per hour), lower speeds (or lower average speed) during a time period (see for example P in Fig. 5D, TG in Fig. 3B) or otherwise, alone or in combination, as well as optionally electrical signals corresponding to one or more of the same. As but one example, any which one of said events would occur as shown in Fig. 20 in lieu of the braking step 106, and similarly sensing of such event(s) would occur in lieu of sensing braking 108, also in Fig. 20. Sending the signal would be done in response to such triggering event to suspend one or more of seat actuators. Each of the other optional features timing parameters, and other variables as discussed above in connection with braking and/or the application of the air bags may be used in connection with one or more of such triggering events.

As but one example setting forth one optional detail such as the events, turning the steering wheel as a triggering event may be further refined by requiring turning of the steering wheel at a certain angular rate per second, total angular displacement, the rate of change of angular velocity (e.g. acceleration of turning of the steering wheel), any combination of these, or otherwise. Additionally, triggering events may be set up in combination. For example, triggering event could include tapping of the brakes in connection with movement of the steering wheel within a certain time period thereof, such as (merely by way of non-limiting example) within less than ten seconds, preferably or less than three seconds of each other. Different optional profiles combining pairs or even more than two of these events may be included. For example, such profiles could optionally include, but not be limited to, such triggering events which correspond, or at least probabilistically correspond to evasive maneuvering of the vehicle, emergency movement or otherwise. For example, a triggering event could be rotational movement of the steering wheel at or above a rate of ten (10) degrees per second. This is by way of example only, and other degrees and other time period parameters may be selected.

Referring to the example shown in the drawings (Fig. 21), a vehicle seating system 130 for reducing user fatigue is shown. The seating system 130 may comprise: a seat having a seat back 26 and a seat bottom 28, a first powered seat adjustment actuator A2 to slowly move said seat back 26 incline slowly forwards and slowly backwards between at least first seat-back position and a second seat-

back position with said slow movement occurring while the vehicle is moving, a first sensor S1 for sensing a first series of speed parameters from said seat back, said first powered seat actuator A2, or both, and a controller C for automatically controlling movement of said first powered seat adjustment actuator A2 while the vehicle is moving wherein said controller C dynamically adjusts the speed of movement of said seat back 26 based on comparing at least one speed parameter from said first series of speed parameters with a first smooth movement speed projection and dynamically adjusting a first control signal to said first powered seat adjustment actuator A2 to converge the speed of movement of said seat back, said first powered seat adjustment actuator A2, or both toward or equal to said first smooth movement speed projection.

Optionally, the seating system 130 may further comprise: a second powered seat adjustment actuator A1 to slowly move said seat bottom 28 tilt slowly up and slowly down between at least first seat-bottom position and a second seat-bottom position with said slow movement occurring while the vehicle is moving, a second sensor S2 for sensing a second series of speed parameters from said seat bottom, said second powered seat actuator A1, or both, and wherein the controller C automatically controls movement of said second powered seat adjustment actuator A1 while the vehicle is moving and dynamically adjusts the speed of movement of said seat bottom 28 based on comparing at least one speed parameter from said second series of speed parameters with a second smooth movement speed projection and dynamically adjusting a second control signal to said second powered seat adjustment actuator A1 to converge the speed of movement of said seat bottom, said second powered seat adjustment actuator A1, or both toward or equal to said second smooth movement speed projection. Note that in Fig. 21, dashed lines are used to depict optional sensed speed parameters.

Optionally, the seating system 130 may further comprise a third powered seat adjustment actuator (not shown for clarity) to slowly move a lumbar region (L on Fig. 1B) of said seat back 26 back and forth between at least first lumbar position and a second lumbar position, said slow movement occurring while the vehicle is moving, a third sensor (not shown for clarity) for sensing a third series of speed parameters from said seat back 26, said third powered seat actuator, or both,

and wherein said controller (C on Fig. 21) automatically controls movement of said third powered seat adjustment actuator while the vehicle is moving and dynamically adjusts the speed of movement of said lumbar region L based on comparing at least one speed parameter from said third series of speed parameters with a third smooth movement speed projection and dynamically adjusting a third control signal to said third powered seat adjustment actuator to converge the speed of movement of said lumbar region, said third powered seat adjustment actuator, or both toward or equal to said third smooth movement speed projection.

The controller C can optionally control the movement of said first powered seat adjustment actuator A2 based on at least the rate of change between at least two speed parameters from said first series of speed parameters. Alternatively, the controller C can optionally control the movement of said first powered seat adjustment actuator A2 based on at least a prior commanded movement of said first powered seat adjustment actuator.

The sensor S can optionally include a hall effect sensor and/or a potentiometer. The hall effect sensor can optionally sense the rotation of a component of said first powered seat adjustment actuator A2. The potentiometer can optionally sense the position of a rotating component of said first powered seat adjustment actuator A2. The first sensor S can optionally sense speed parameters at an average sampling rate greater than or equal to 100 Hertz. Optionally, the sampling rate can also be greater than or equal to 1 kilohertz or 10 kilohertz for increased accuracy. The controller C can also optionally be configured to implement a proportional integral derivative control function.

Optionally, the first powered seat adjustment actuator A2 can include an electric motor and the first control signal can be a pulse width modulated signal with a duty cycle adjusted to alter the speed of rotation of the electric motor. An example pulse width modulated signal is shown in Fig. 23A with t representing the time that the pulse width modulated signal is active and T representing the total time of the square wave cycle. Fig. 23B shows an example output signal from a hall effect sensor with three segments X, Y, and Z corresponding to different speeds. Fig. 23C shows an example and optional control schema wherein an example hall effect output signal is shown below example duty cycles that the

actuator is commanded to operate at. For this example, at segment A the actuator is started at the preceding duty cycle it was commanded to operate at, at segment B the duty cycle of the actuator is increased to overcome increased friction in the system, at segment C the friction in the system decreases, at segment D the duty cycle of the actuator is reduced to compensate for the reduced friction, at segment E the load on the system is increased, and finally at segment F the duty cycle of the actuator is increased to compensate for the increased load.

The first smooth movement speed projection can optionally be an envelope set by minimum and maximum values, a single set of target values as a function of time or displacement, predefined and include a constant speed segment, and/or predefined and include non-linear speed at its beginning, end, or both.

Examples of speed projection profiles overlaid with series of speed parameters are shown in Figs. 22A-22D. Figs. 22A-22C show three time segments A, B, and C which correspond to the actuator being inactive, active, and inactive respectively. For these example figures, the X axis corresponds to time and the Y axis corresponds to speed. An example ideal smooth movement speed projection 900 is shown in Fig 22A. The example ideal smooth movement speed projection 900 gradually moves from rest to a target speed, the speed is constant at the target speed throughout the segment that the actuator is commanded active, and the speed gradually returns to rest. Figs. 22A and 22B also depict an example envelope 903 set by minimum and maximum values corresponding to an optional smooth speed projection. Fig 22B shows an example series of speed parameters following within this optional envelope 901 when using the invention. Another series of speed parameters is shown falling outside of the envelope when the seating system is not used 902. Fig. 22D shows an example more detailed view of the actuator being active (time segment B). Element 3750 specifically shows an example speed parameter falling outside of the envelope when the seating system is not used.

As used here (claims, specification, and other definitions) the following terms have the following meaning:

Articles and phases such as, “the”, “a”, “an”, “at least one”, and “a first”, “comprising”, “having” and “including” here are not limited to mean only one, but rather are inclusive and open ended to also include, optionally, two or more of such

elements and/or other elements. In terms of the meaning of words or terms or phrases herein, literal differences therein are not superfluous and have different meaning, and are not to be synonymous with words or terms or phrases in the same or other claims.

5 The term "and/or" is inclusive here, meaning "and" as well as "or". For example, "P and/or Q" encompasses, P, Q, and P with Q; and, such "P and/or Q" may include other elements as well.

 The term "average sampling rate" as used herein means the mean frequency at which samples are taken and defines the number of samples per unit of time
10 taken from a continuous signal.

 The term "compare" as used herein means to measure or estimate the degree of dissimilarity or similarity between at least two values or series of values, or between at least two values that are correlated to said value or series of values. In computer syntax, this may include without limitation operators such as for
15 example: IF ($x < y$), IF ($x > y$), IF ($x = y$), IF BETWEEN, and others.

 The phrase "consisting essentially of" means specified materials and/or ingredient and/or steps and/or acts and/or other elements, and to those that do not materially affect the invention's basic and novel characteristics in the claim (as a transition) or the element or the group.

20 The phrase "consisting of" means to only include exactly what is stated, and excludes any step, act, material ingredient, or element not specified in the claim (as a transition) or the element or the group, but does not necessarily require the absence of trace amounts (less than 1% by weight) of impurities.

 The term "constant speed segment" as used herein means a portion of the
25 smooth movement speed projection that is held constant, i.e. the speed value does not change. Graphically, this is represented by a horizontal line when the Y axis of the graph represents speed and the X axis represents time or displacement.

 The term "control signal" as used herein means a signal applied to a controlled object from a controller. The signal may be wired or not. The signal
30 may be electrical, electronic, optical, RF or otherwise. Examples of control signals include pulse width modulated, frequency modulated, and amplitude modulated

electrical or optical signals. Control signals may optionally also contain electrical power provided to the object.

The term “converge the speed” as used herein means to bring two values or two series of values closer to each other in terms of speed.

5 The term “duty cycle” as used herein means the ratio of a measure of time that a pulse width modulated signal is active to the total time of the square wave cycle that the active signal was measured from. A cycle contains an active portion and an inactive portion. Note that the period of the square wave does not have to be constant and therefore each cycle of the waveform can have a different cycle
10 time.

The term “dynamically adjust” as used herein means to adjust something at or very near the time it is moving or changing.

The term “electric motor” as used herein means an electric machine that converts electrical energy into rotating mechanical energy. Examples of electric
15 motors include brushed DC motors, brushless DC motors, uncommutated DC motors, permanent magnet DC motors, synchronous AC motors, induction AC motors, and stepper motors.

The term “envelope” as used herein means a representation of the area between two curves on a graph. One of said curves represents the minimum values
20 and the other the maximum values. When used to define a smooth movement speed projection for an object, the envelope defines an area representing the set of target values for the speed of the object.

The term “function of time or displacement” as used herein means a relationship or expression involving the variable of time or displacement.

25 The term “hall effect sensor” as used herein means any sensor that sense a magnetic field and provides an output in response to such a field.

The term “implement” as used herein means to fulfill, perform, or carry out. Examples of implementing a proportional integral derivative control function include the use of a logic device such as a microcontroller, microprocessor, FPGA,
30 or CPLD. Additionally, a proportional integral derivative control function can be implemented with discrete components such as capacitors, inductors, resistors, and transistors.

The term “means” and/or “means for” and/or “step” and/or “step for” here, if and when used in a claim, invokes 35 U.S.C. §112(f) means-plus-function for the recited function(s) and the corresponding structure(s) or act(s)(including alternatives in the definitions or elsewhere in this disclosure) and equivalents thereto.

The term “non-linear speed” as used herein means a speed that varies.

The term “potentiometer” as used herein means a variable resistor with a third adjustable terminal. The potential at the third terminal can be adjusted to vary the resistance across the variable resistor. Examples of detecting the rotation of a component utilizing a potentiometer include mounting the potentiometer such that its third adjustable terminal is adjusted in accordance with the movement of an axle or a gear of an electric motor. Knowing the correlation between the resistance of the potentiometer and the position of the third terminal, the change in position of the electric motor axle or gear can be sensed for a given period of time.

The term “predefined” as used herein means established in advance. This includes being pre-programmed and/or stored in ROM, PROM or other computer memory. This also includes components that are utilized to store values, such as voltage dividers, resistors, or other discrete components.

The term “proportional integral derivative control function” as used herein means a control loop feedback mechanism that calculates an "error" value as the difference between a measured process variable (such as the speed of the seat back) and a desired setpoint value (such as the smooth motion speed profile). The function attempts to minimize the error by adjusting the process control output(s) (such as the control signal to the actuator).

The term “pulse width modulated signal” as used herein means a square wave signal with the proportion of time when the square wave is active to when it is inactive is varied in order to change the average value of the signal. In other words, the duty cycle of the signal is modulated.

The term “rate of change” as used herein means the amount of which a variable changes over a specific period of time. Examples of rate of change include velocity as the rate of change of position, and acceleration as the rate of change of velocity.

The term “rotating component” as used herein means an element that moves circularly around an axis or center, whether by rotation or revolution. Examples of rotating components include gears, axes, discs, arms, and magnets.

5 The term “rotation of a component” as used herein means the general movement of a component circularly around an axis or center, whether by rotation or by revolution. Examples of detecting the rotation of a component utilizing a hall effect sensor include placing a magnetized element onto a rotating component and sensing either the pulse width of the hall effect sensor output and/or the frequency of the hall effect sensor output. Examples or rotating components
10 include gears, axes, discs, arms, and magnets (in the case of the rotating component itself being a magnetic, no separate magnetized element is required).

The term “sensor” as used herein means a device that senses or measures a speed parameter and records, indicates, or otherwise responds to it. Examples of sensors include, but are not limited to, a hall effect sensor, a potentiometer, an
15 encoder (linear, rotary, and/or optical), an accelerometer, a tilt sensor, a rangefinder, an inclinometer, a photodiode, motion detector, or a combination of any of the previous.

The term “series” as used herein means more than one in squence. When a series of speed parameters is sensed, it means that at least two speed parameters are
20 sensed by the sensor at different times.

The term “single set of target values” as used herein means that, unlike the envelope approach, the smooth movement speed projection is represented by one curve or line or plot when graphed. This contains all of the target values for the speed of the object that the smooth movement speed projection pertains to.

25 The term “speed parameter” as used herein means a physical attribute that can be measured to derive the speed (linear, curvilinear or rotary) of an object. Examples of speed parameters include speed, velocity, acceleration, displacement and/or position.

The term “smooth movement speed projection” as used herein means a
30 forecasted value or series of forecasted values that correspond to an actuator’s movement that would be smooth, such that movement is not jarring or jerky.

The invention may include any one or more articles or devices made by any of the claimed methods and/or may be made by different methods but with a claimed composition.

5 The language used in the claims and the written description and in the above definitions is to only have its plain and ordinary meaning, except for terms explicitly defined above. Such plain and ordinary meaning is defined here as inclusive of all consistent dictionary definitions from the most recently published (on the filing date of this document) general purpose Webster's dictionaries and Random House dictionaries.

10 While the disclosure has been illustrated and described in detail in the drawings and foregoing description, the same is to be considered as illustrative and not restrictive in character, it being understood that only the preferred embodiment has been shown and described and that all changes and modifications that come within the spirit of the disclosure are desired to be protected.

15

What is claimed is:

1. A vehicle seating system for reducing user fatigue, comprising:
 - a seat having a seat back and a seat bottom;
 - 5 a first powered seat adjustment actuator to slowly move said seat back incline slowly forwards and slowly backwards between at least first seat-back position and a second seat-back position, said slow movement occurring while the vehicle is moving;
 - a first sensor for sensing a first series of speed parameters from said seat
 - 10 back, said first powered seat actuator, or both; and,
 - a controller for automatically controlling movement of said first powered seat adjustment actuator while the vehicle is moving, wherein said controller dynamically adjusts the speed of movement of said seat back based on comparing at
 - 15 least one speed parameter from said first series of speed parameters with a first smooth movement speed projection and dynamically adjusting a first control signal to said first powered seat adjustment actuator to converge the speed of movement of said seat back, said first powered seat adjustment actuator, or both toward or equal to said first smooth movement speed projection.
- 20 2. The system of claim 1, and further comprising:
 - a second powered seat adjustment actuator to slowly move said seat bottom
 - tilt slowly up and slowly down between at least first seat-bottom position and a
 - second seat-bottom position, said slow movement occurring while the vehicle is
 - moving;
 - 25 a second sensor for sensing a second series of speed parameters from said seat bottom, said second powered seat actuator, or both; and,
 - wherein said controller automatically controls movement of said second powered seat adjustment actuator while the vehicle is moving and dynamically
 - adjusts the speed of movement of said seat bottom based on comparing at least one
 - 30 speed parameter from said second series of speed parameters with a second smooth movement speed projection and dynamically adjusting a second control signal to said second powered seat adjustment actuator to converge the speed of movement

of said seat bottom, said second powered seat adjustment actuator, or both toward or equal to said second smooth movement speed projection.

3. The system claim 1, wherein said controller controls the movement
5 of said first powered seat adjustment actuator based on at least the rate of change between at least two speed parameters from said first series of speed parameters.

4. The system of claim 1, wherein said first sensor includes a hall
effect sensor.

10

5. The system of claim 4 wherein said hall effect sensor senses rotation of a component of said first powered seat adjustment actuator.

6. The system of claim 1, wherein said first sensor includes a
15 potentiometer.

7. The system of claim 6, wherein said potentiometer senses the position of a rotating component of said first powered seat adjustment actuator.

20 8. The system of claim 1, wherein said first powered seat adjustment actuator includes an electric motor; and,

wherein said first control signal is a pulse width modulated signal and a duty cycle of said pulse width modulated signal is adjusted to alter the speed of rotation of said electric motor.

25

9. The system of claim 1 wherein said controller is configured to implement a proportional integral derivative control function.

10. The system of claim 1, wherein the first smooth movement speed
30 projection is an envelope set by minimum and maximum values.

11. The system of claim 1, wherein the first smooth movement speed projection is a single set of target values as a function of time or displacement.

12. The system of claim 1, wherein the first smooth movement speed projection is predefined and includes a constant speed segment.

13. The system of claim 1, wherein the first smooth movement speed projection is predefined and includes non-linear speed at its beginning, end, or both.

10

14. The system of claim 1, wherein said controller controls the movement of said first powered seat adjustment actuator based on at least a prior commanded movement of said first powered seat adjustment actuator.

15

15. The system of claim 1, and further comprising:

a third powered seat adjustment actuator to slowly move a lumbar region of said seat back back and forth between at least first lumbar position and a second lumbar position, said slow movement occurring while the vehicle is moving;

20 a third sensor for sensing a third series of speed parameters from said seat back, said third powered seat actuator, or both; and,

wherein said controller automatically controls movement of said third powered seat adjustment actuator while the vehicle is moving and dynamically adjusts the speed of movement of said lumbar region based on comparing at least one speed parameter from said third series of speed parameters with a third smooth movement speed projection and dynamically adjusting a third control signal to said third powered seat adjustment actuator to converge the speed of movement of said lumbar region, said third powered seat adjustment actuator, or both toward or equal to said third smooth movement speed projection.

25

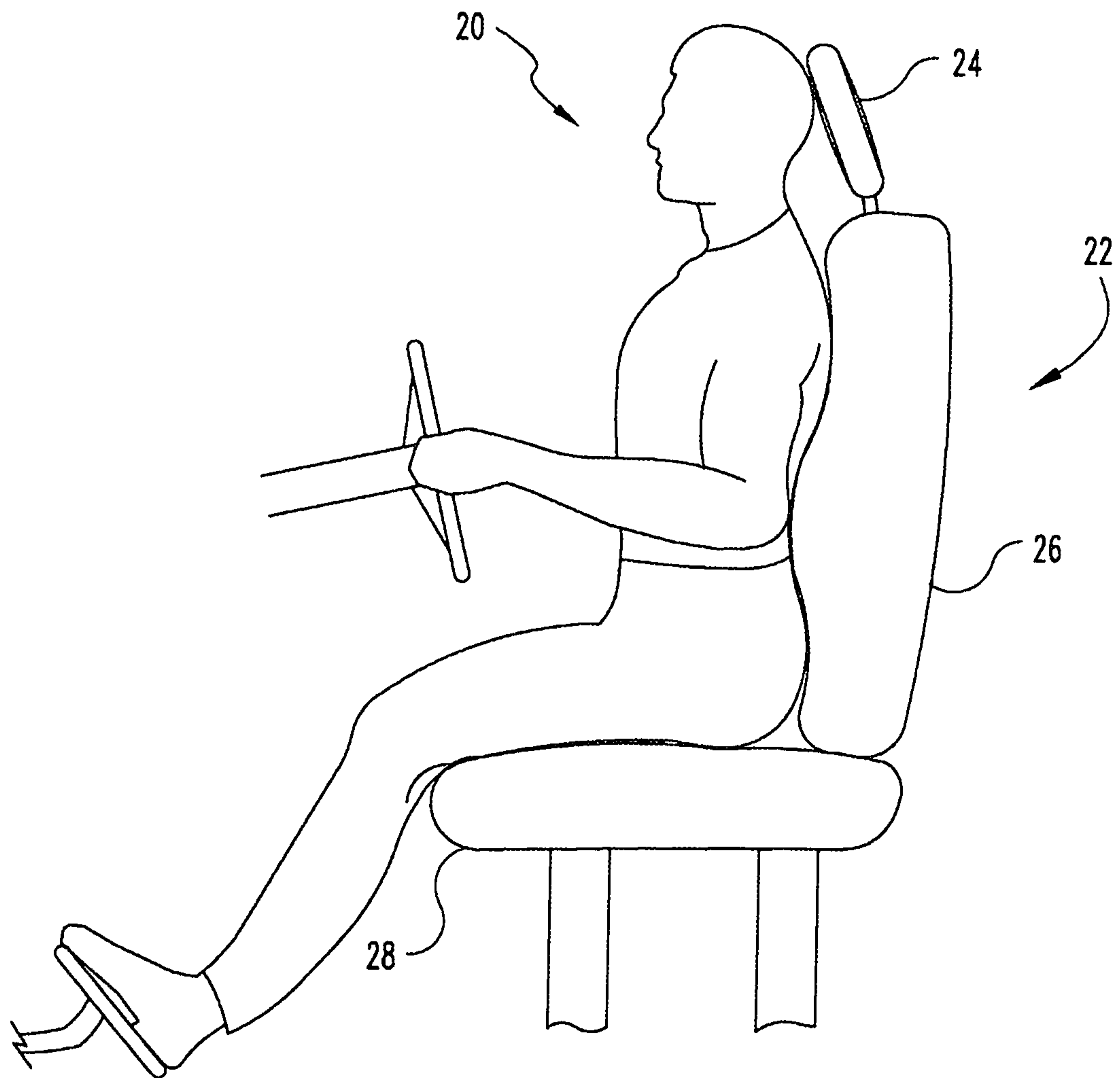


Fig. 1A

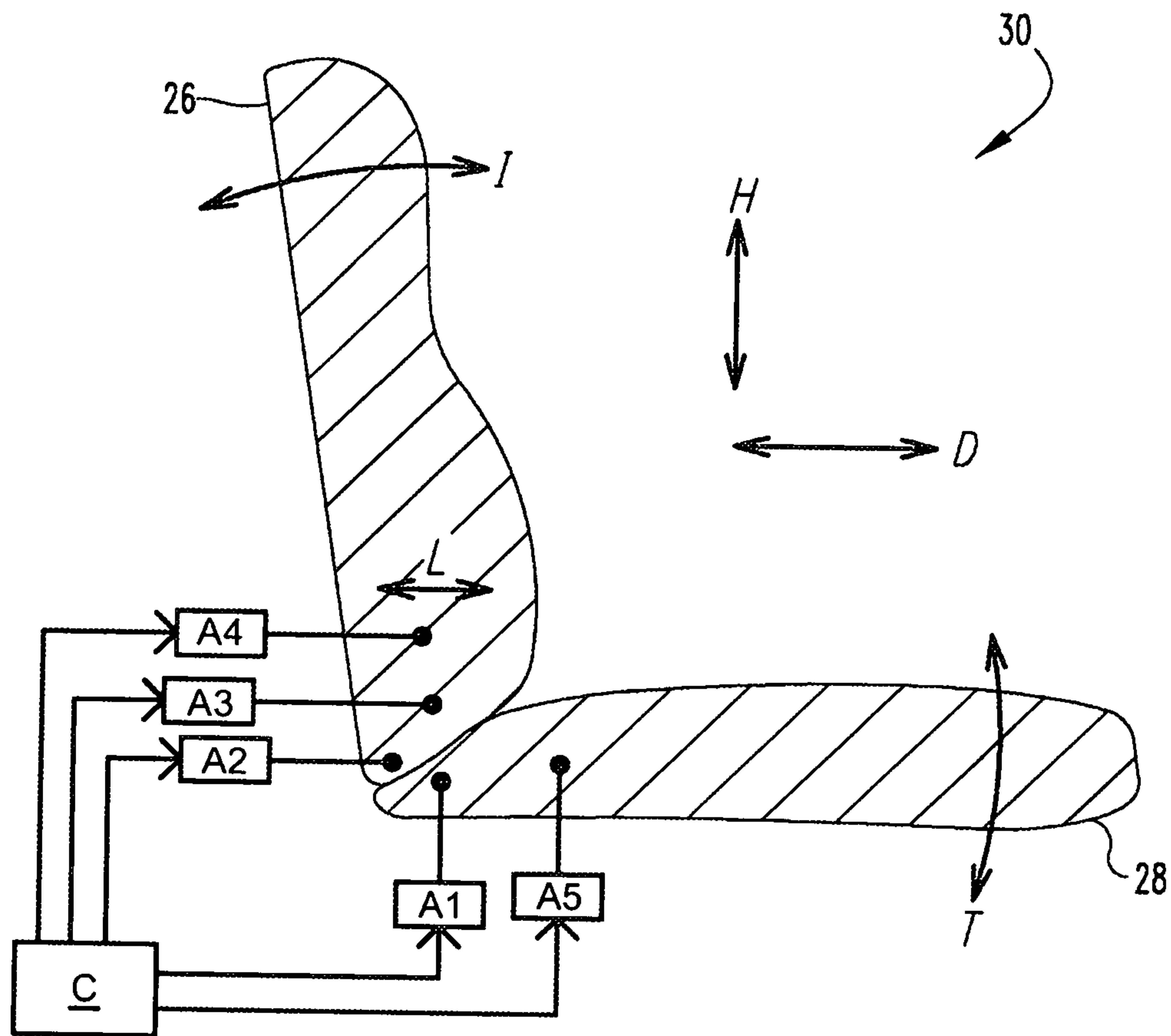


Fig. 1B

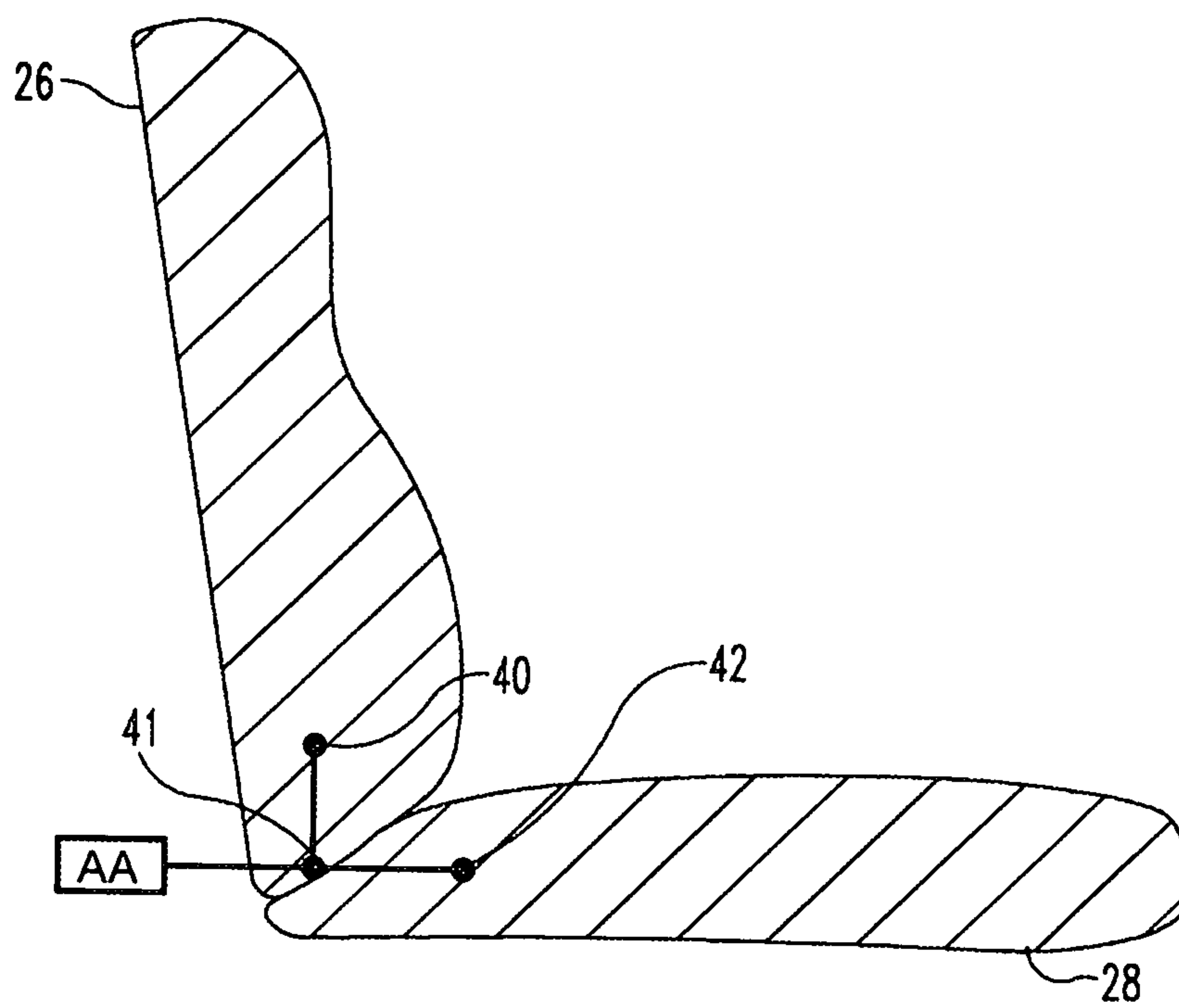


Fig. 1C

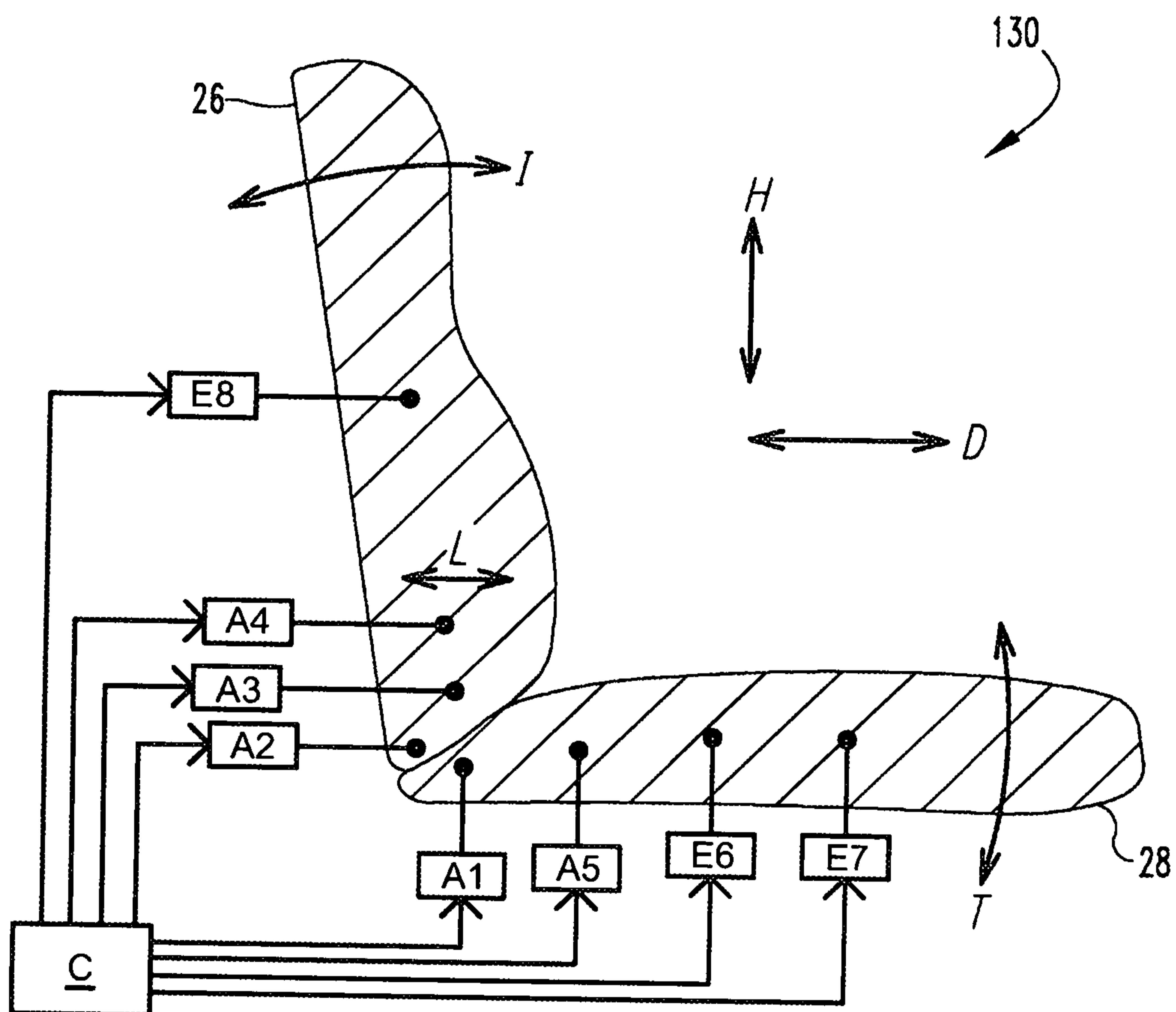


Fig. 1D

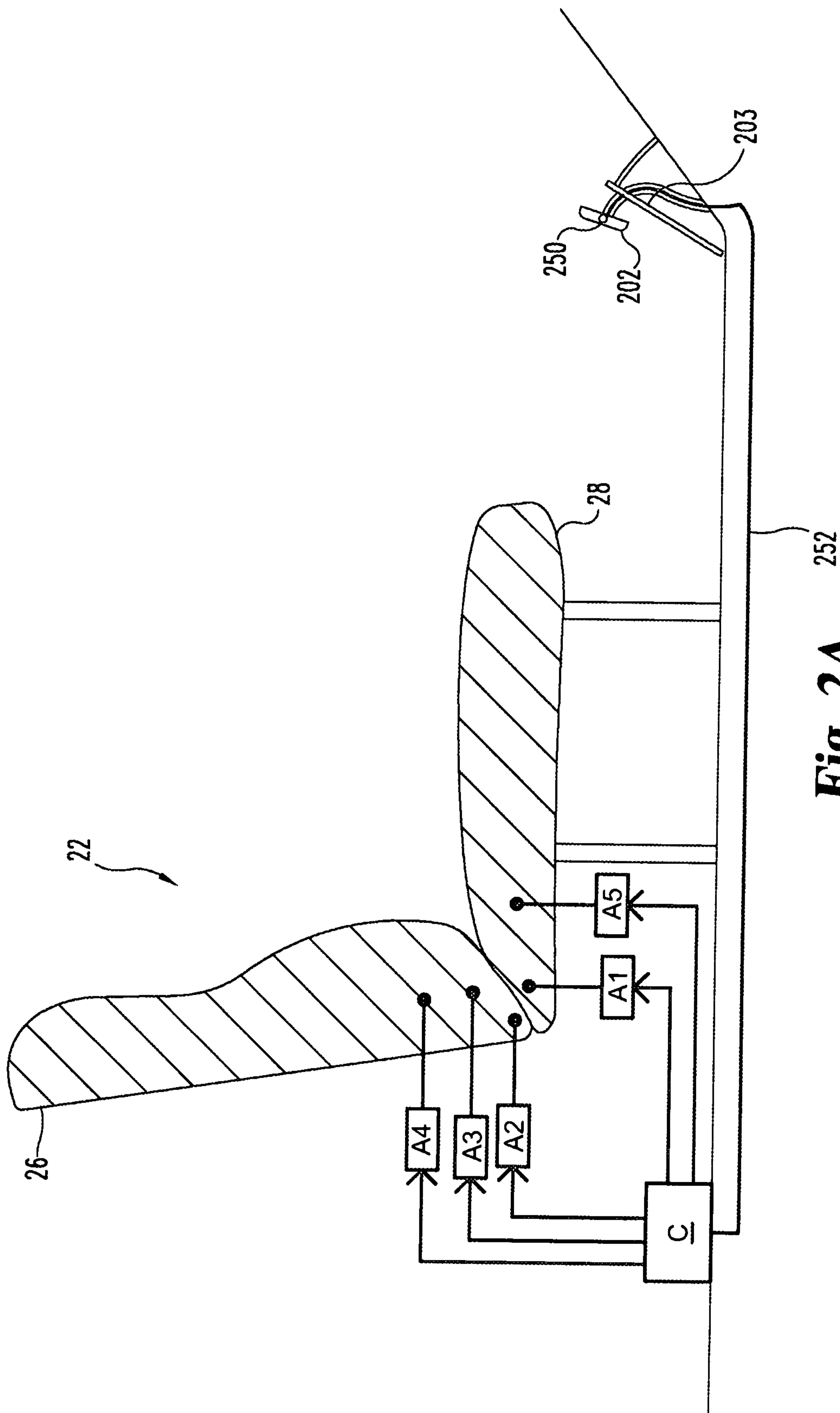


Fig. 2A

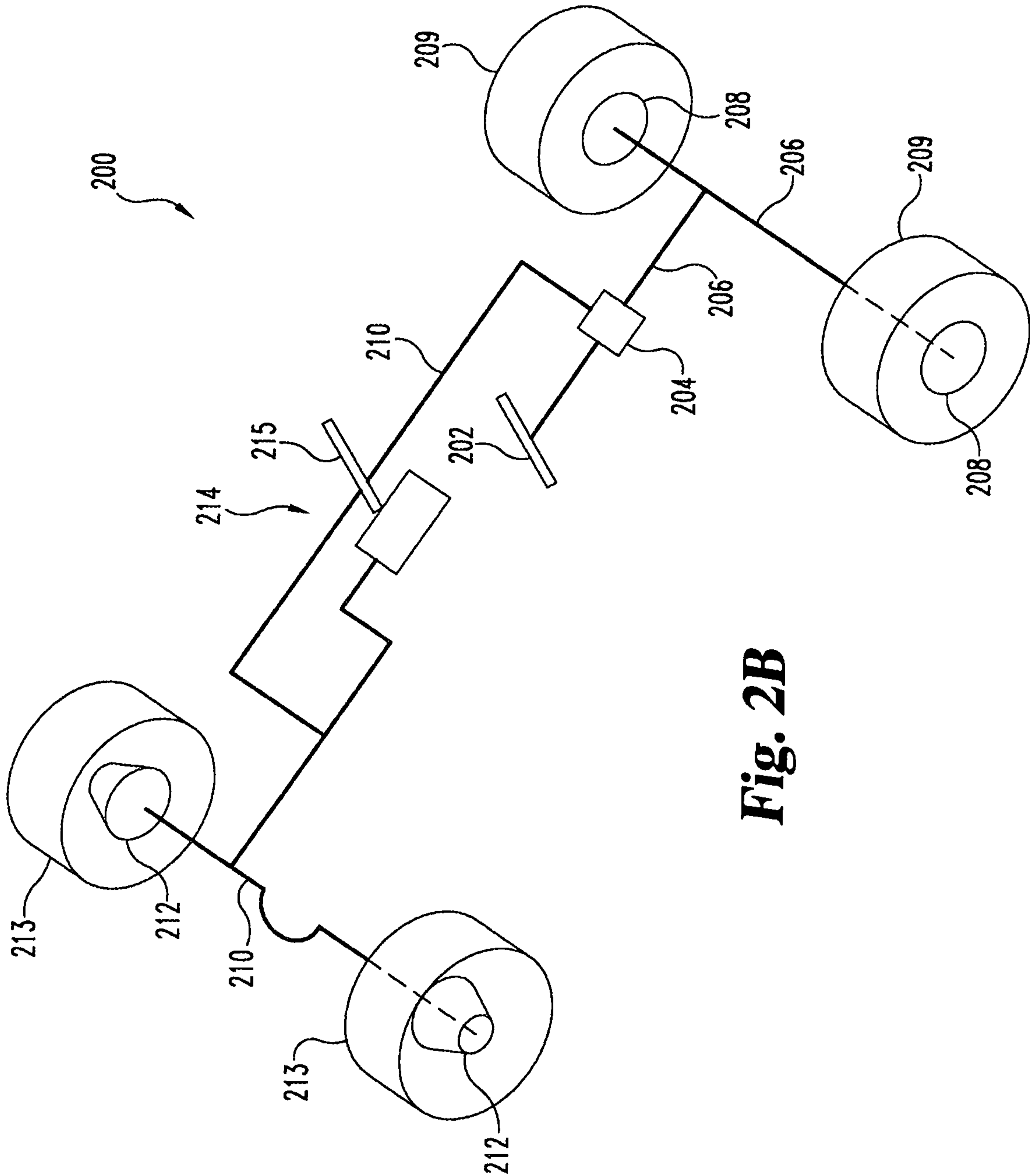
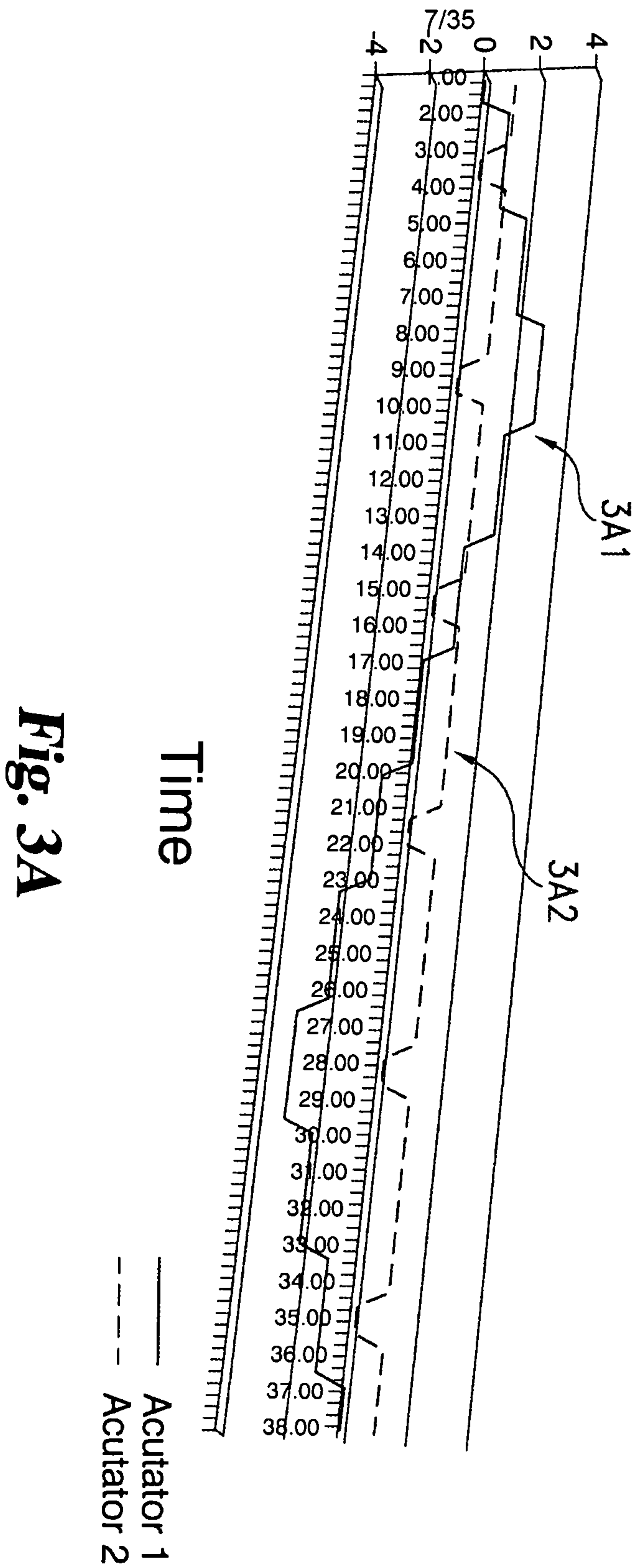
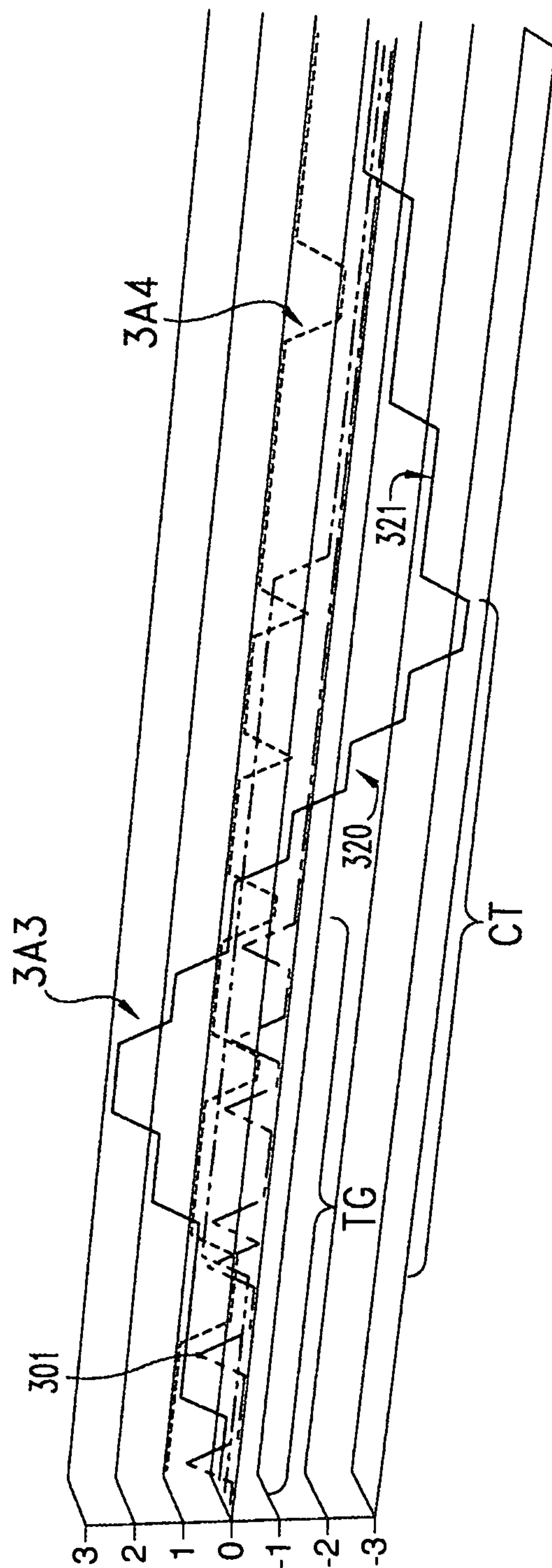


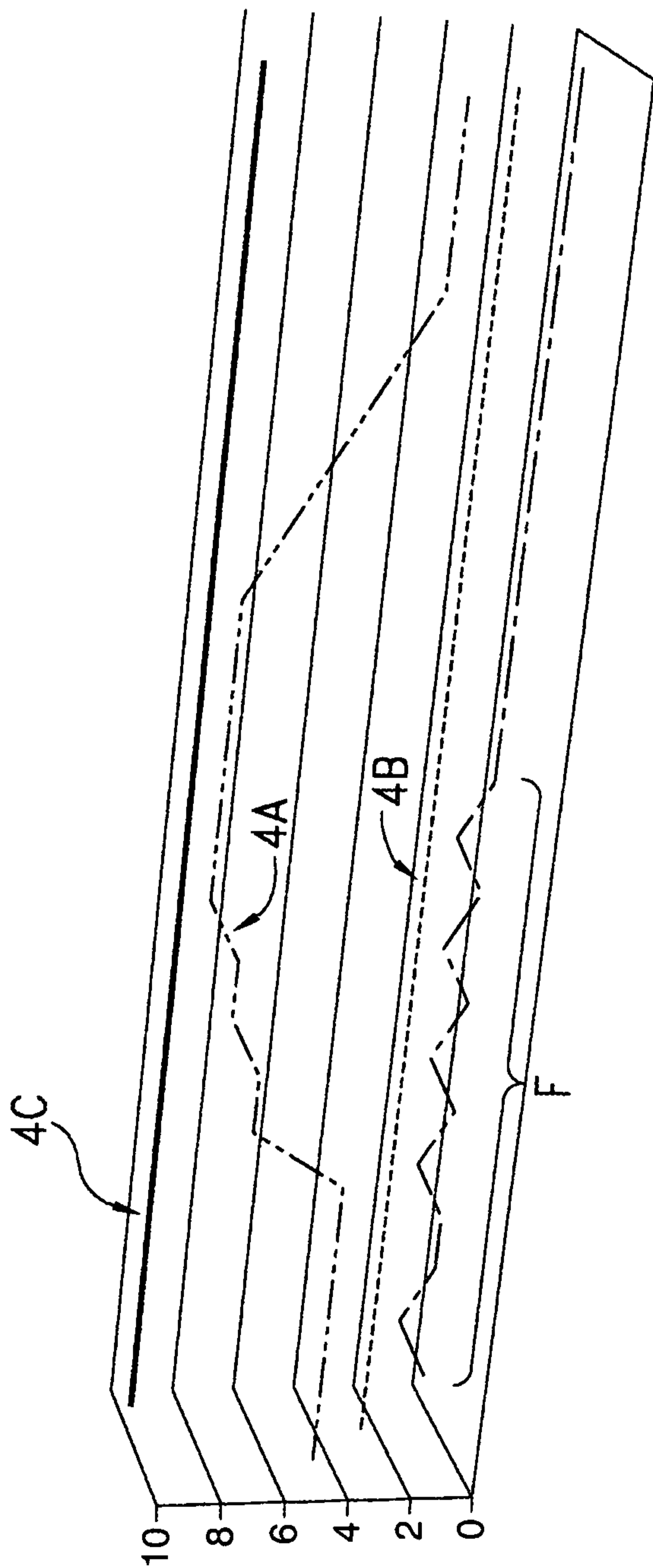
Fig. 2B





- Trigger
- - - City Mode
- Actuator 1
- Actuator 2

Fig. 3B



- Acuator 1 Intensity
- - - Acuator 2 Intensity
- - - Acuator 3 Intensity
- . - Fatigue Indicator

Fig. 4

10/35

Movement

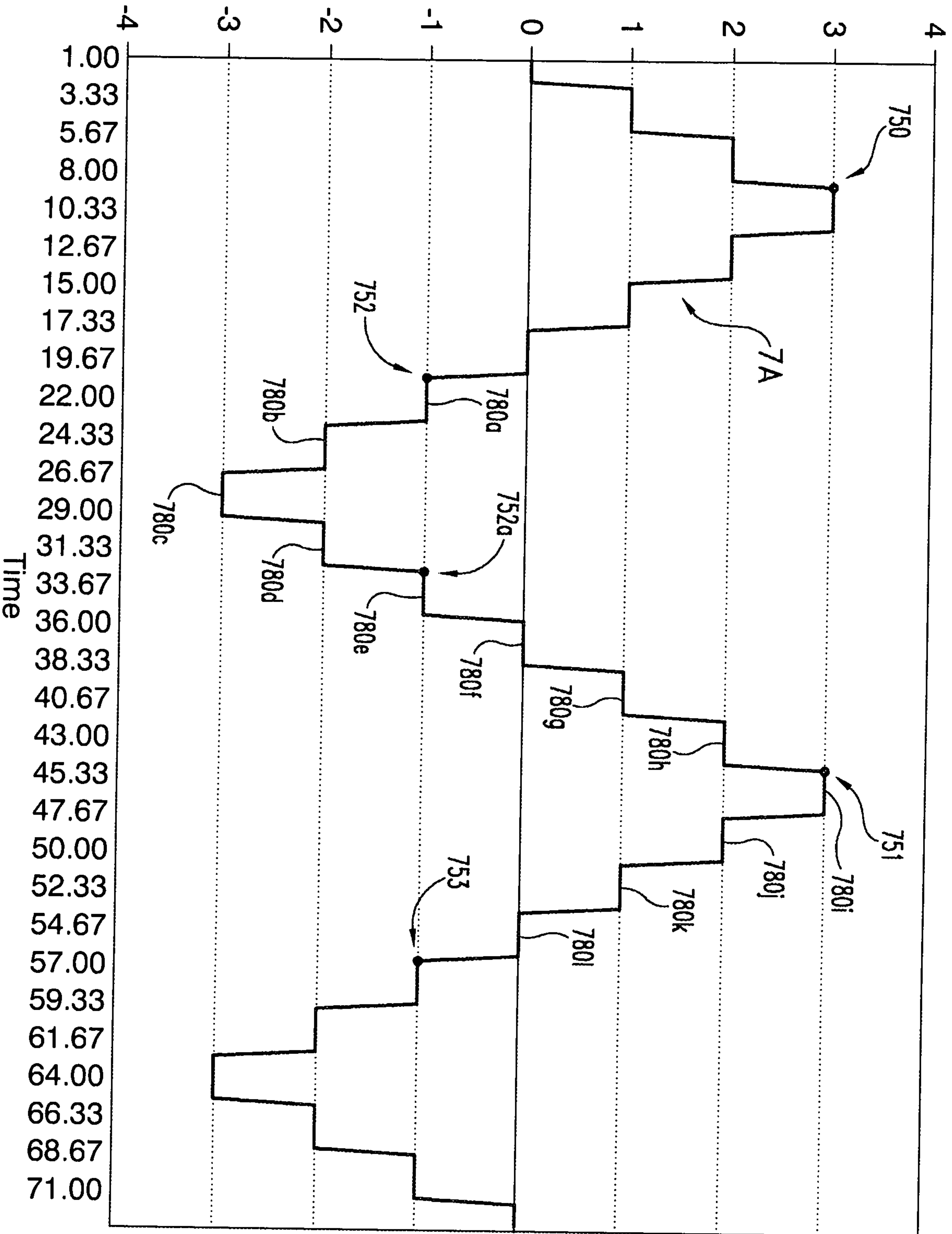


Fig. 5A

11/35

Movement

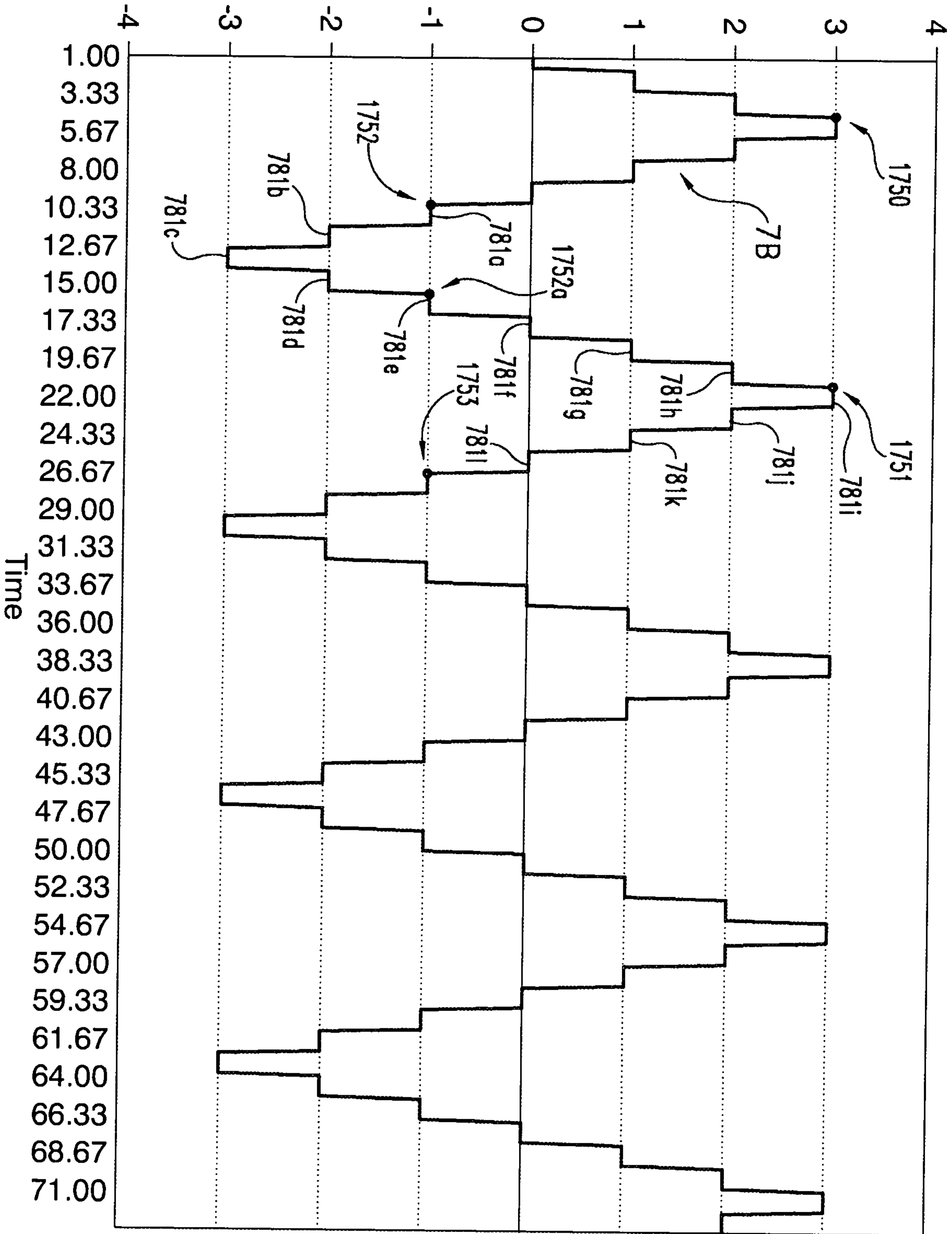


Fig. 5B

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Movement

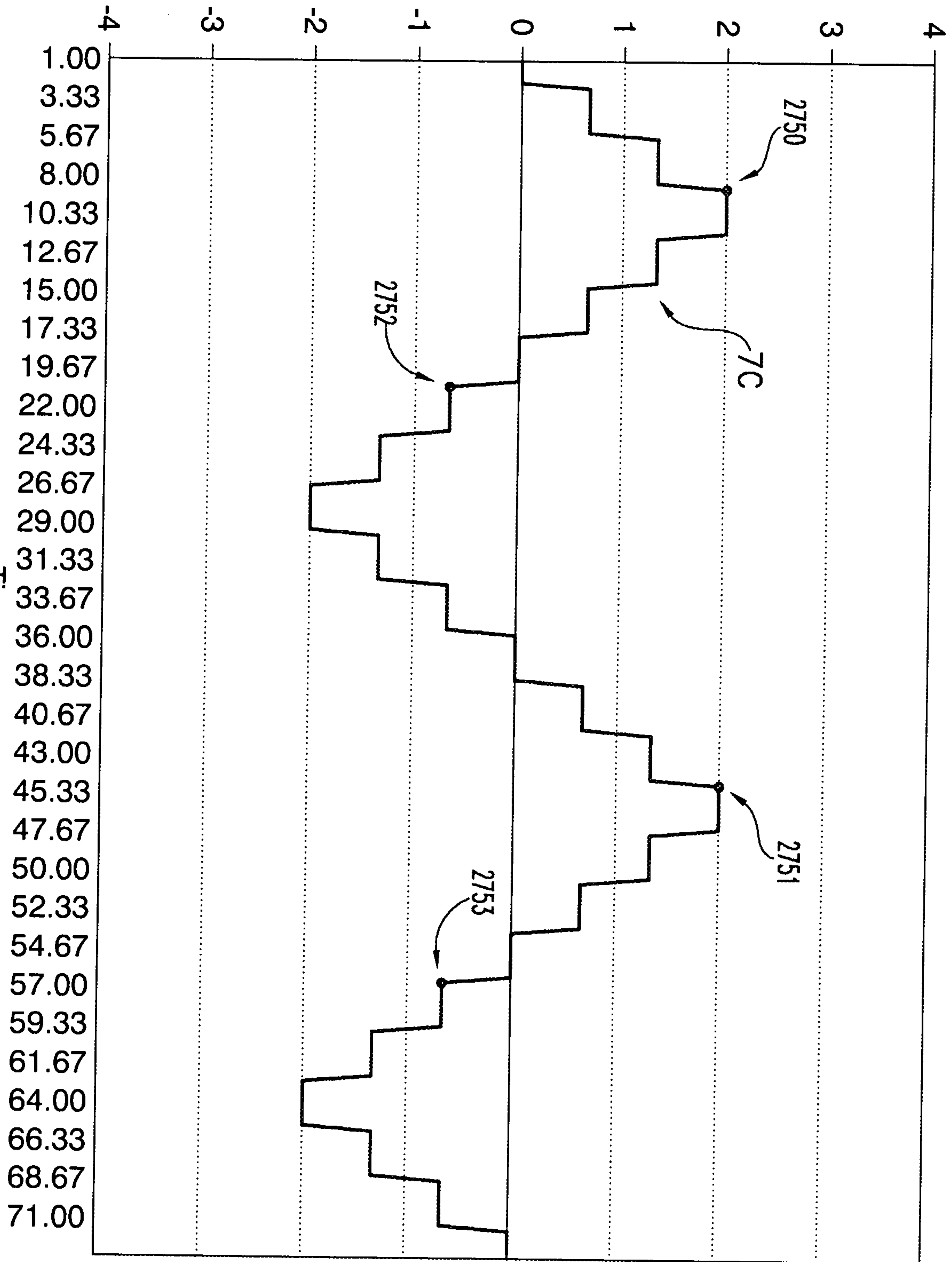


Fig. 5C

Movement

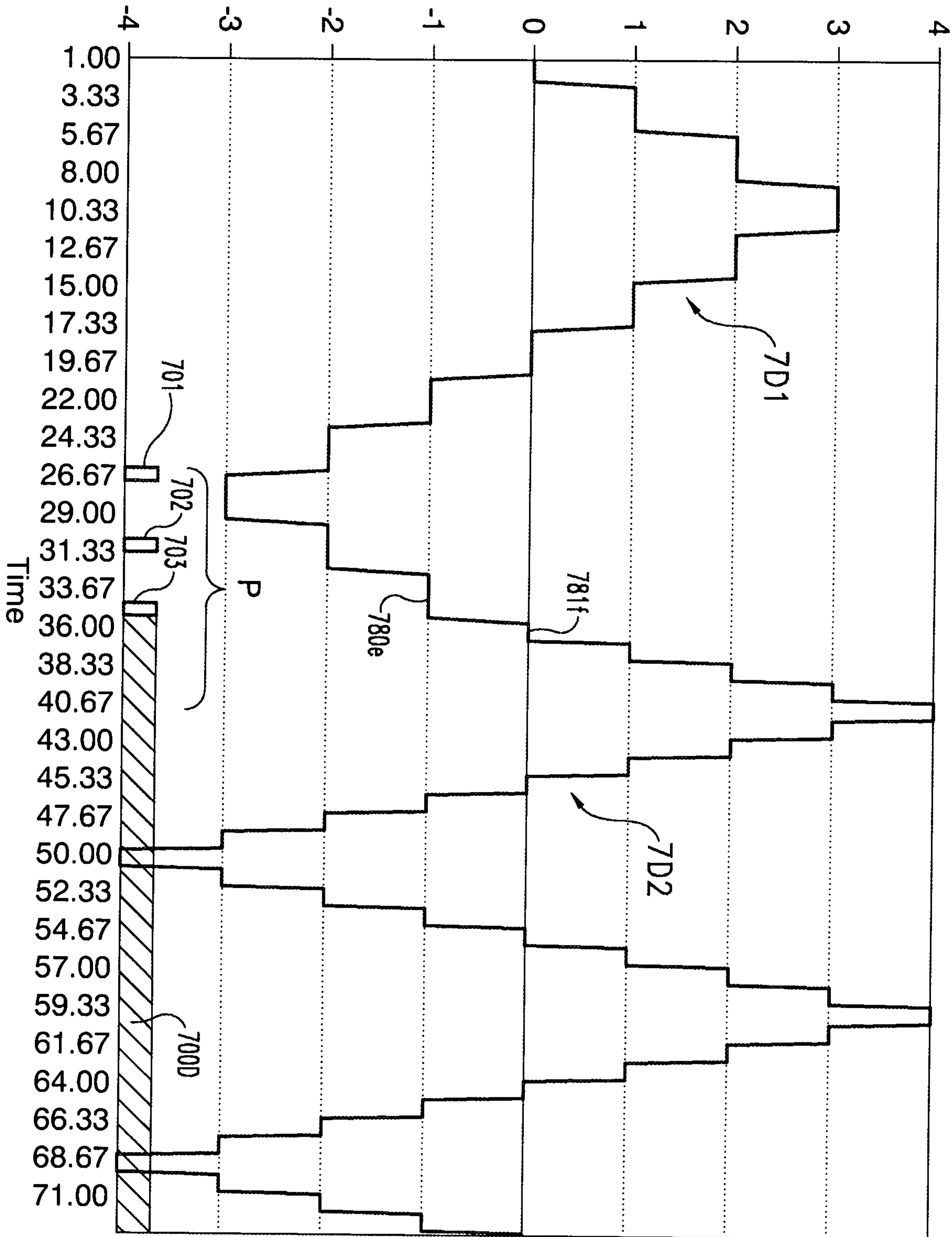


Fig. 5D

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Movement

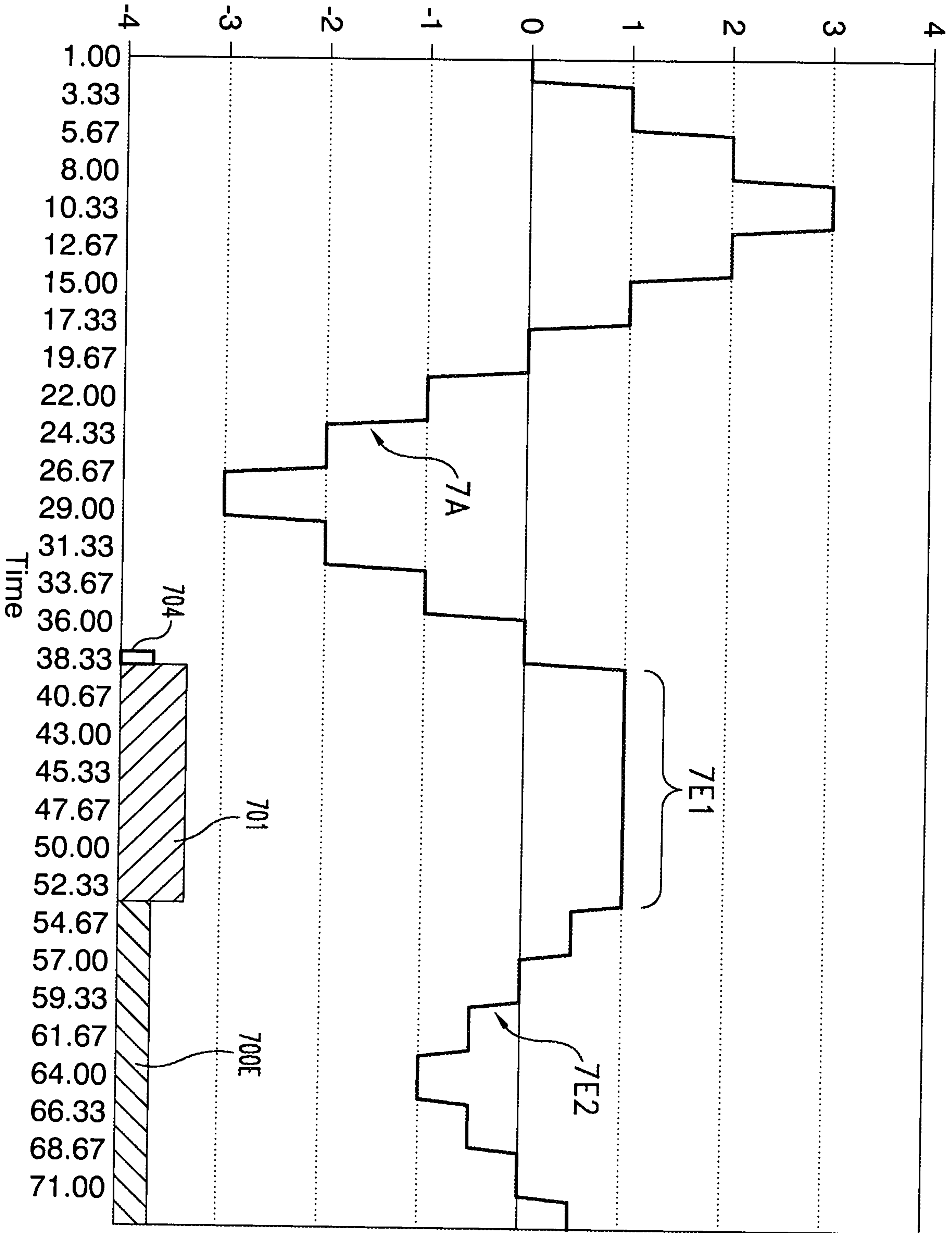


Fig. 5E

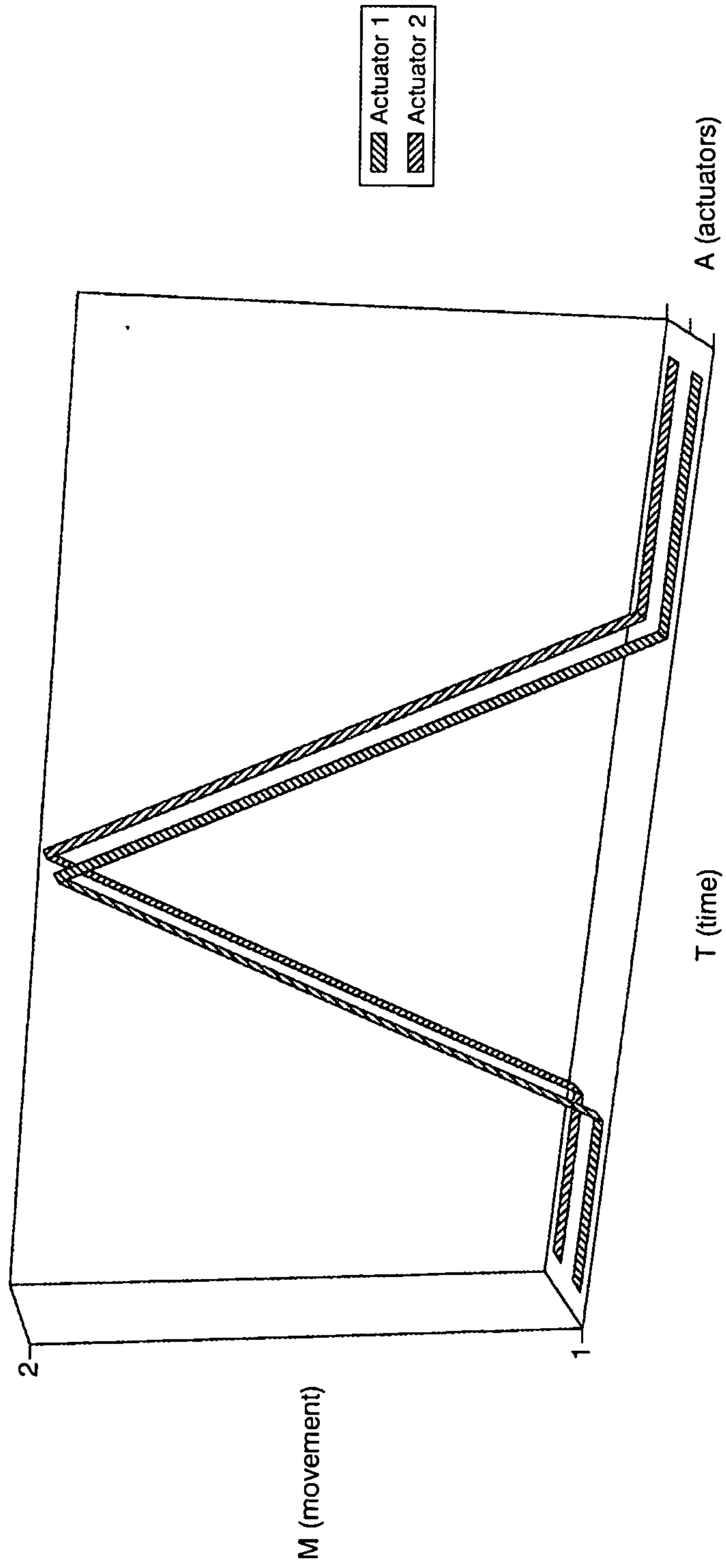


Fig. 6

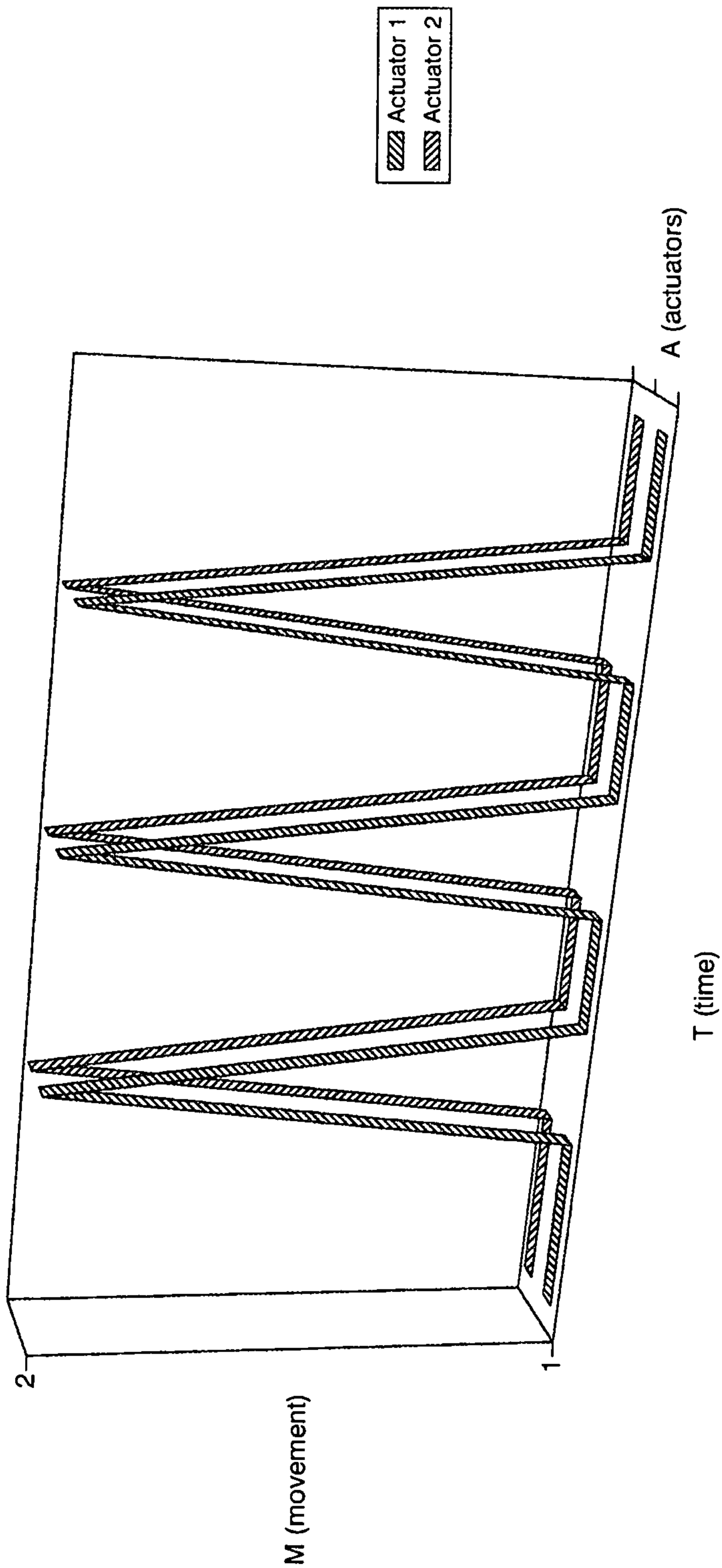


Fig. 7

17/35

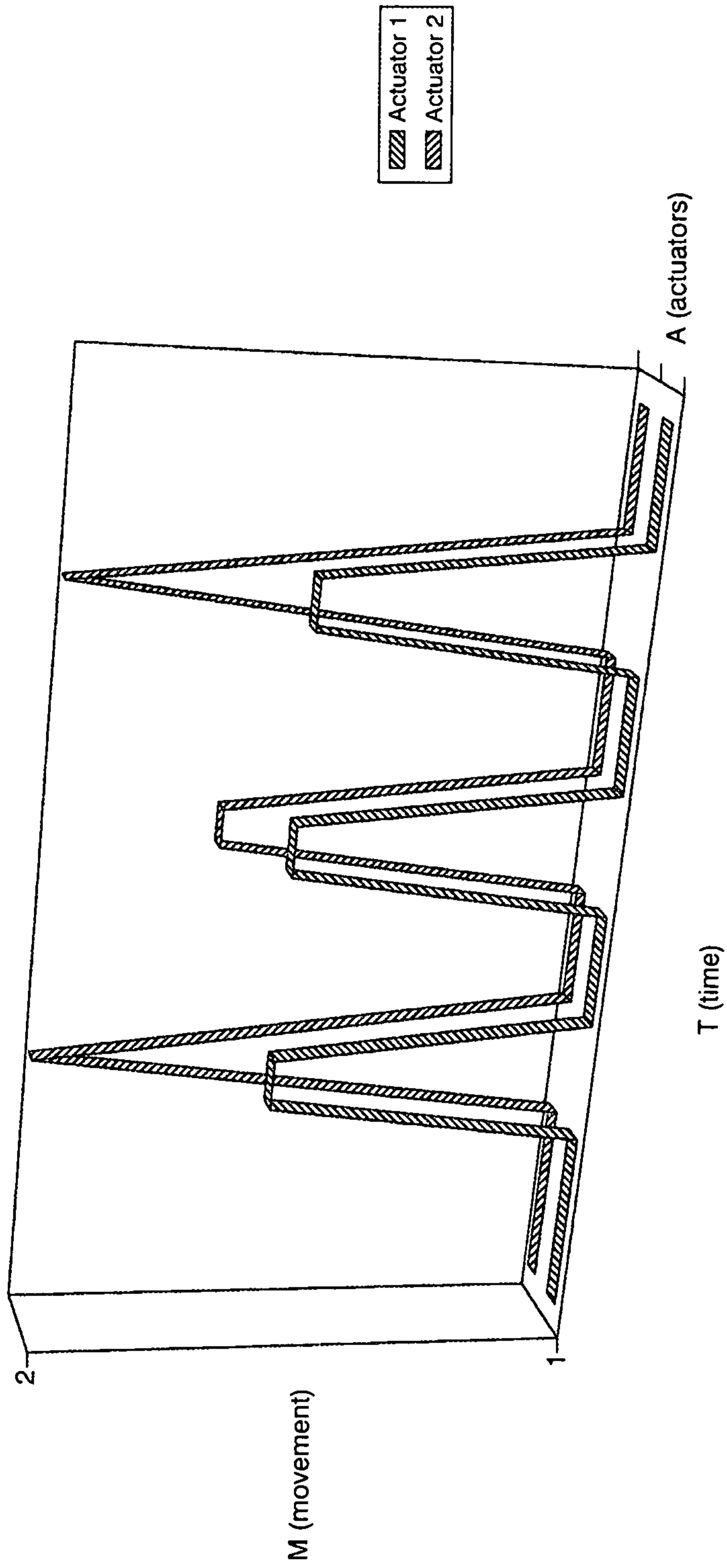


Fig. 8

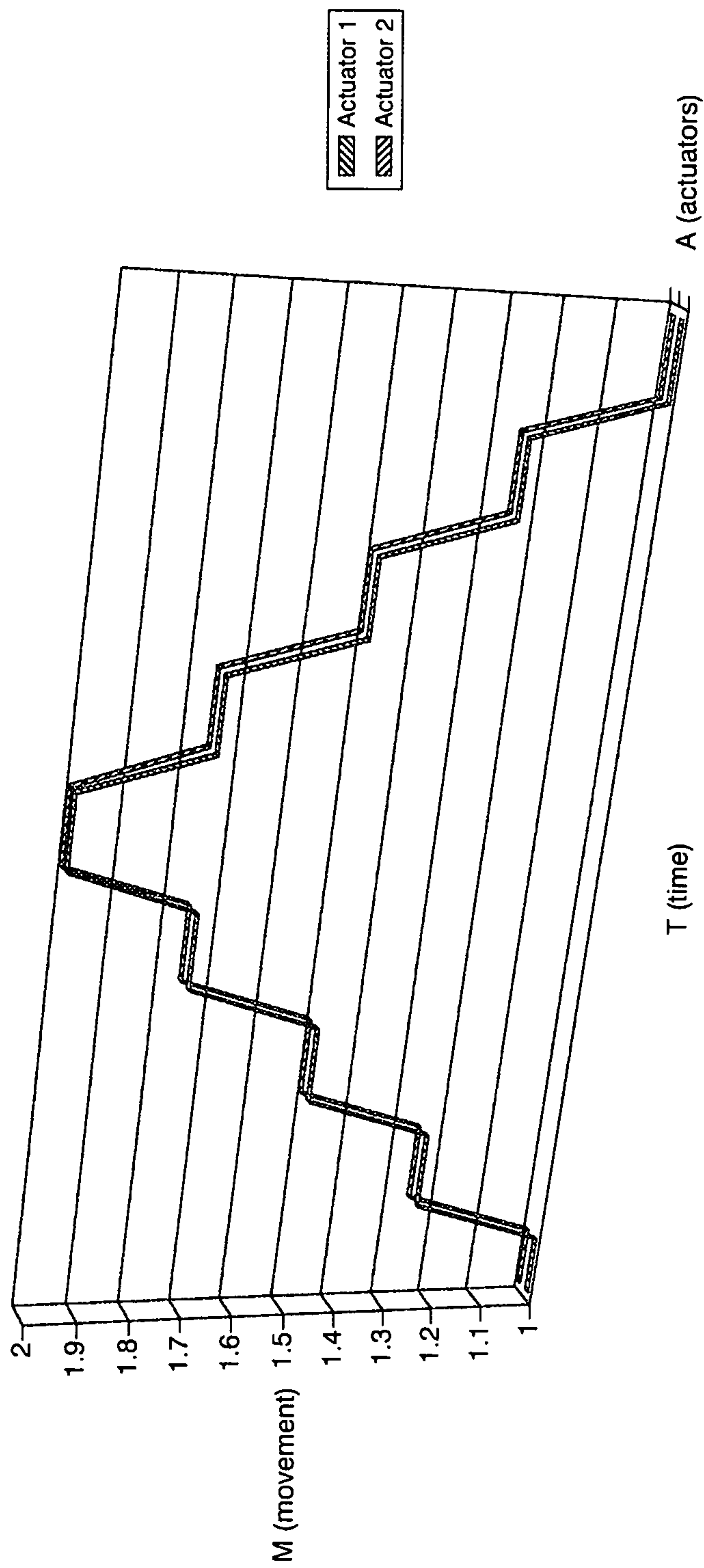


Fig. 9

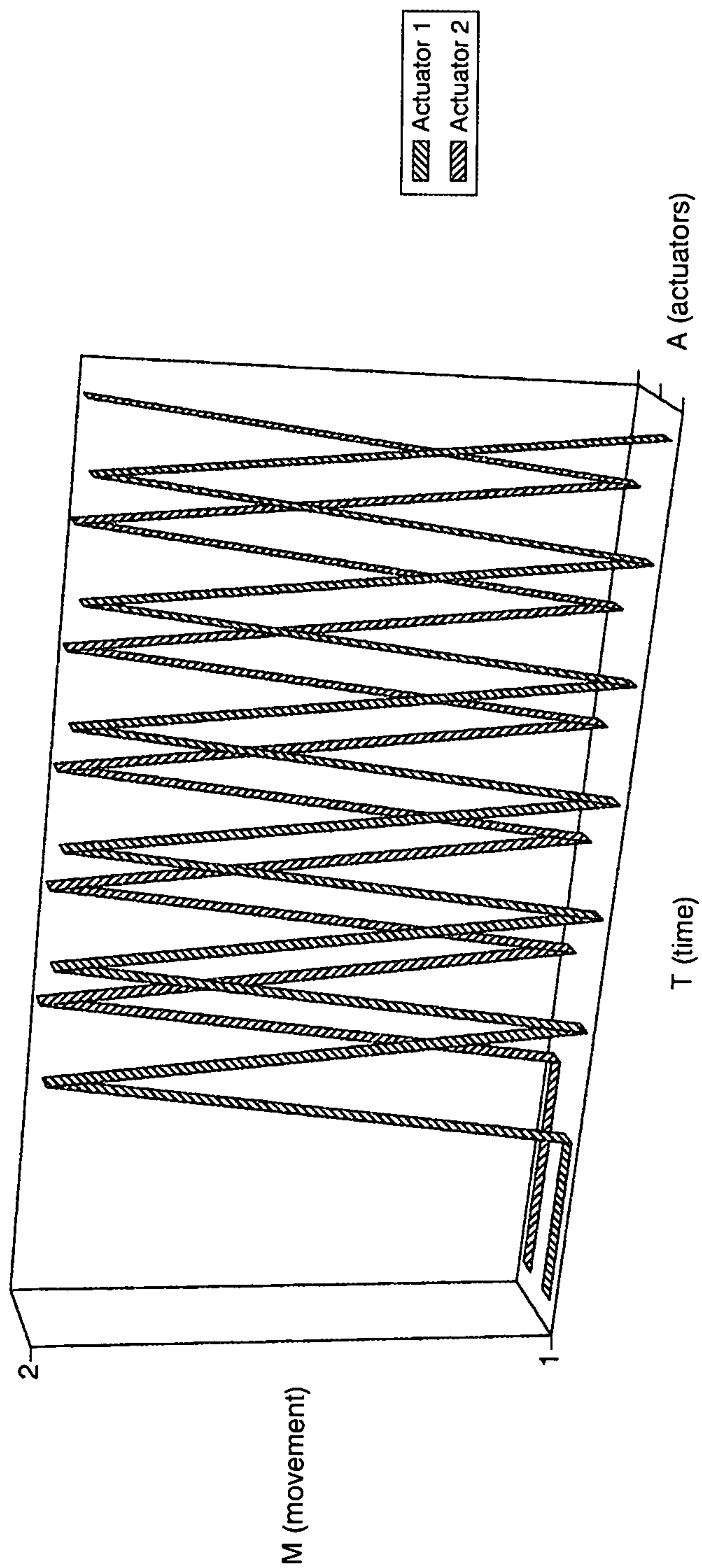


Fig. 10

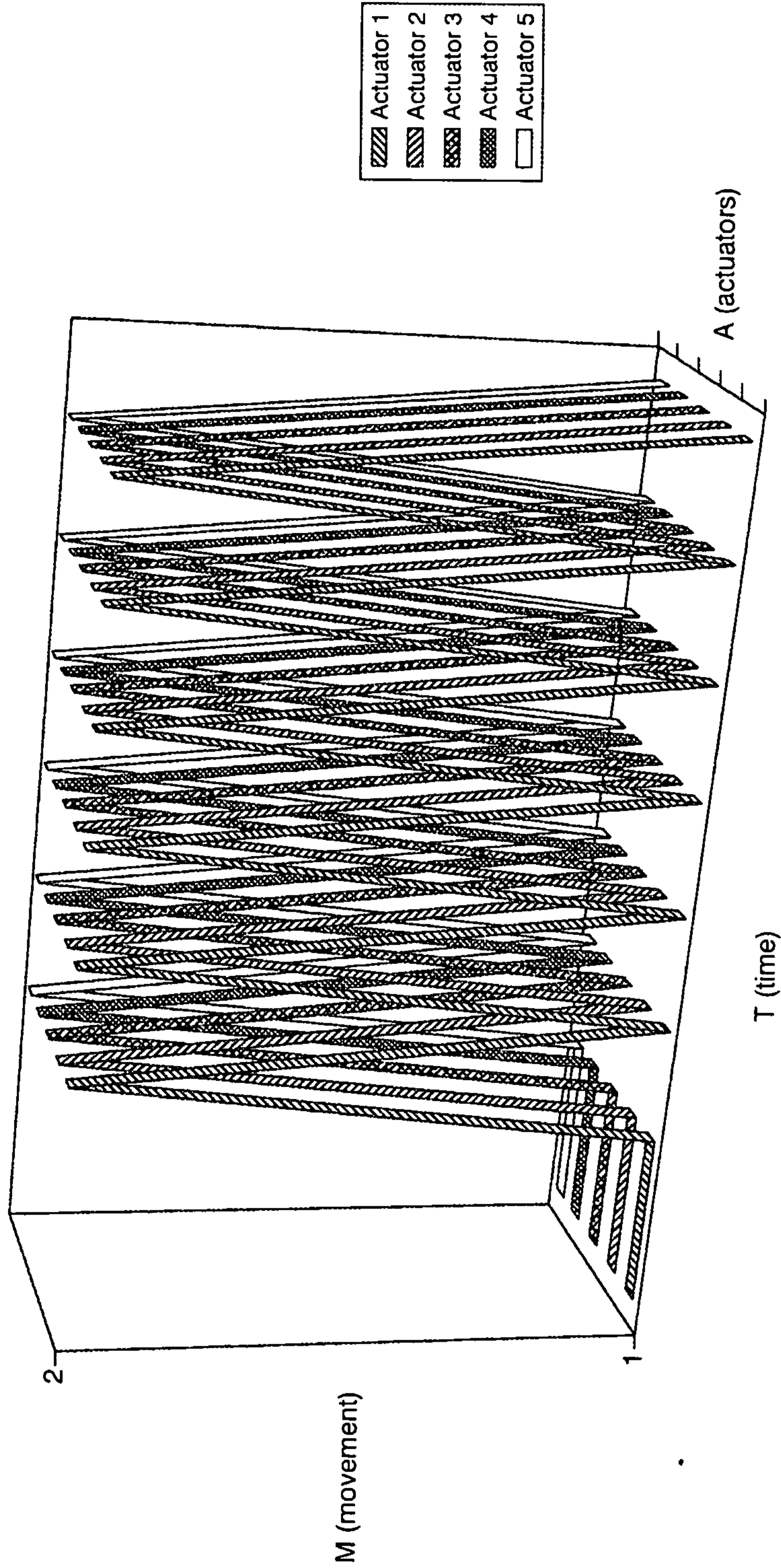


Fig. 11

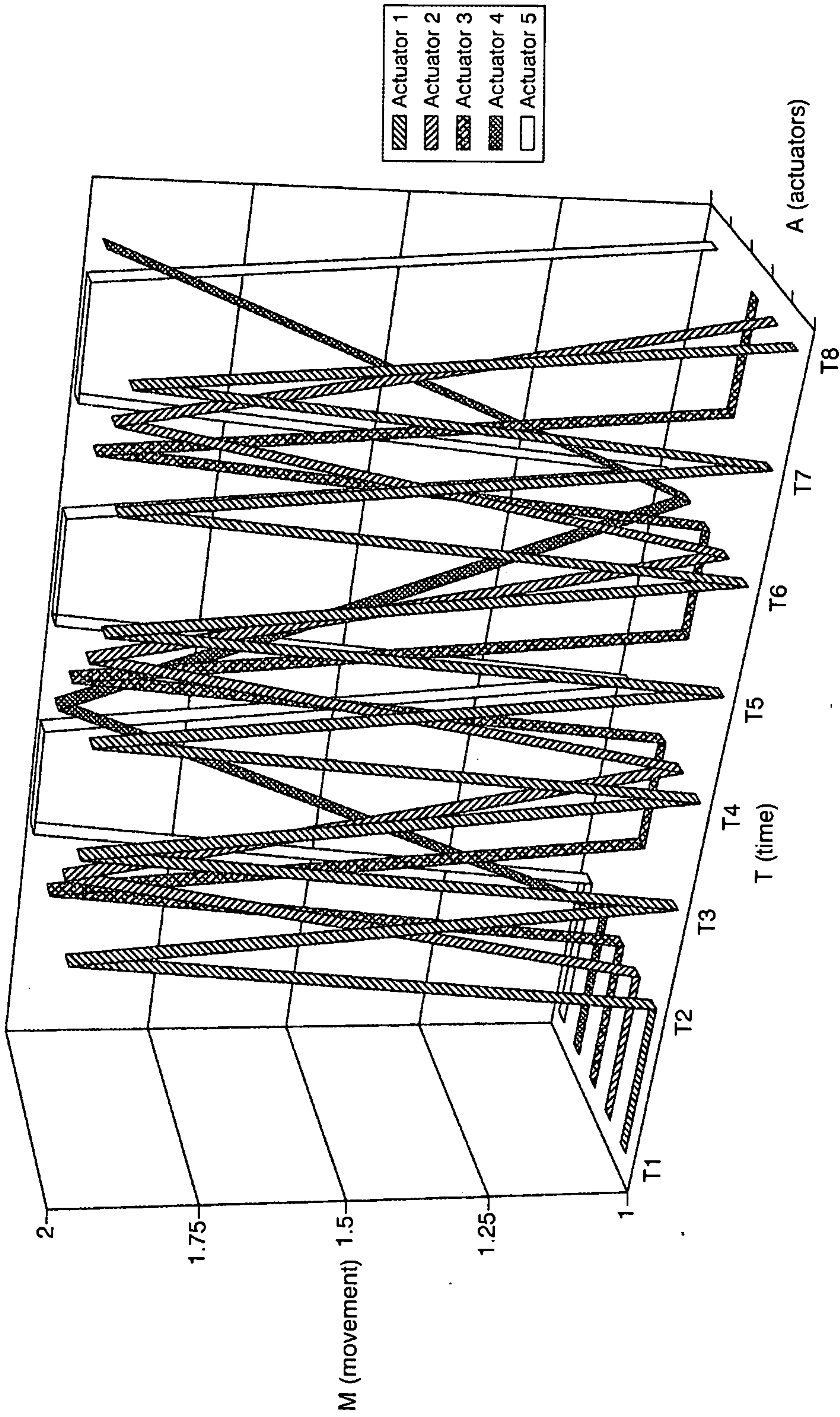


Fig. 12

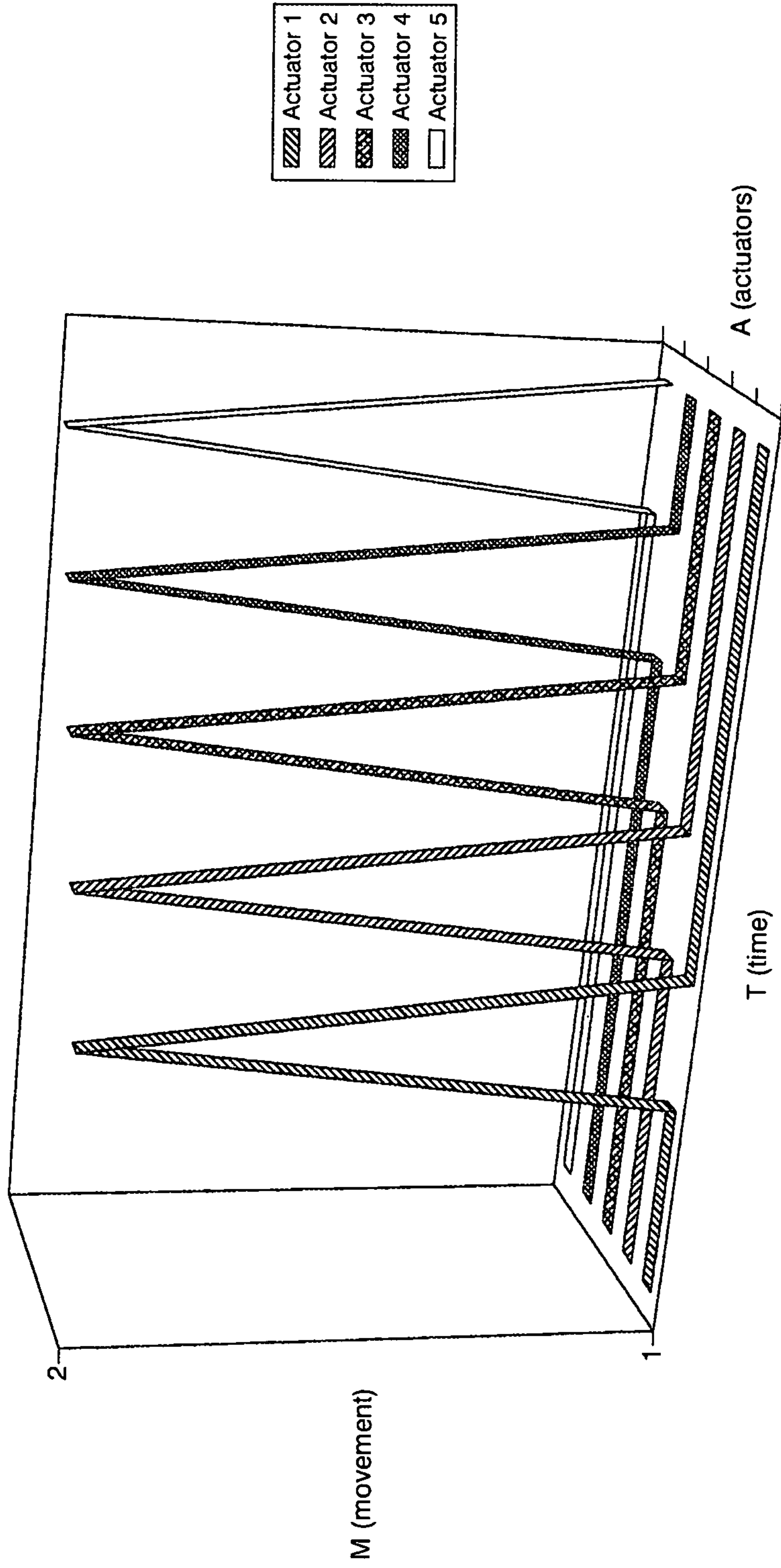


Fig. 13

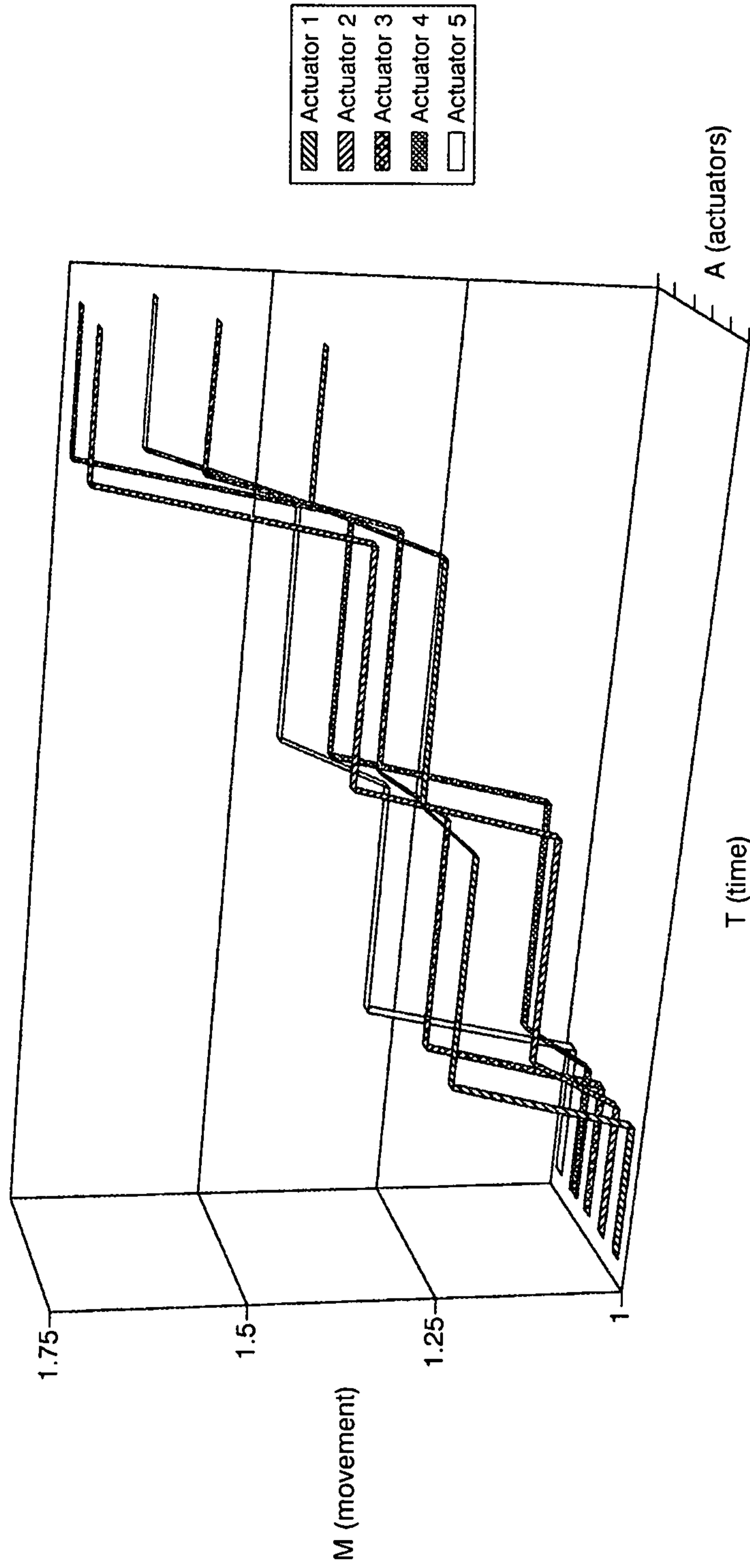


Fig. 14

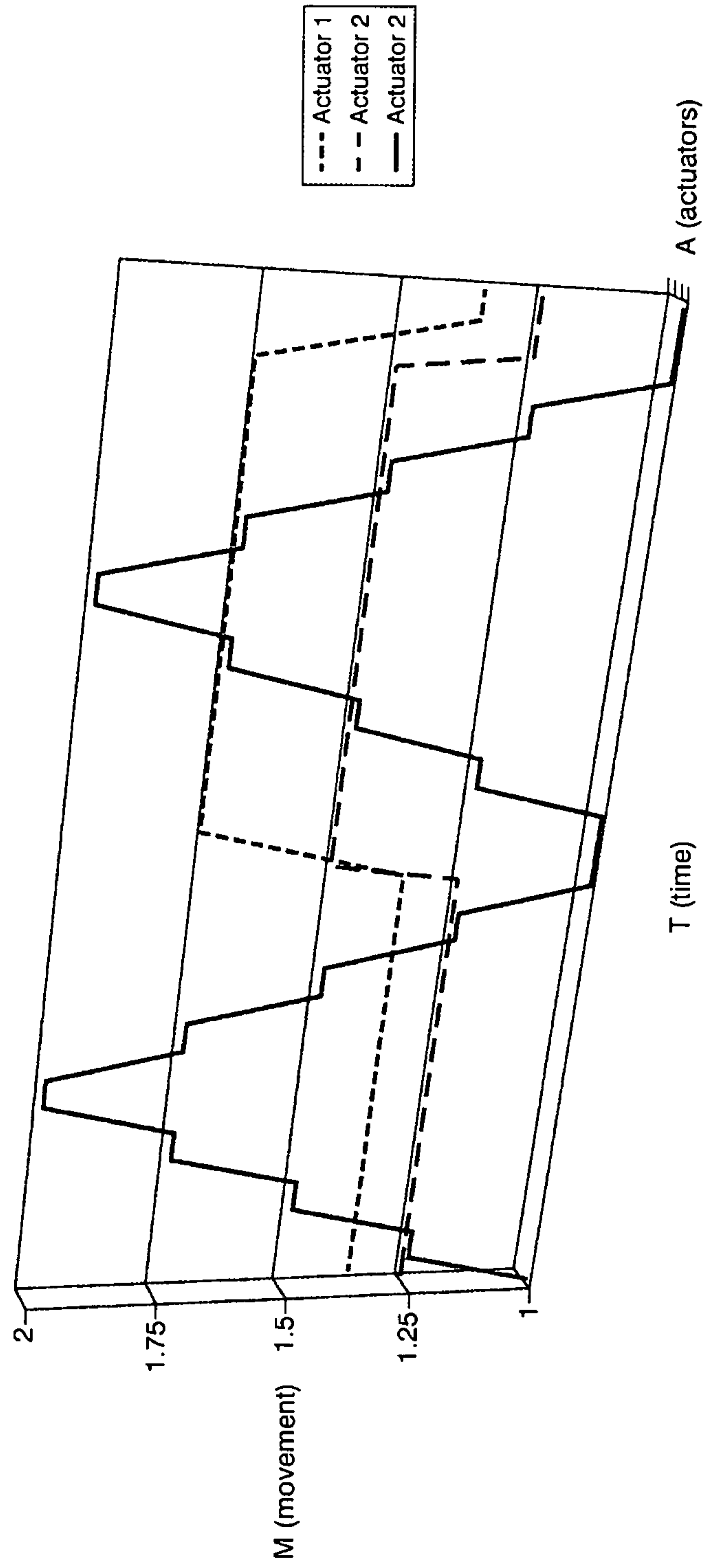


Fig. 15

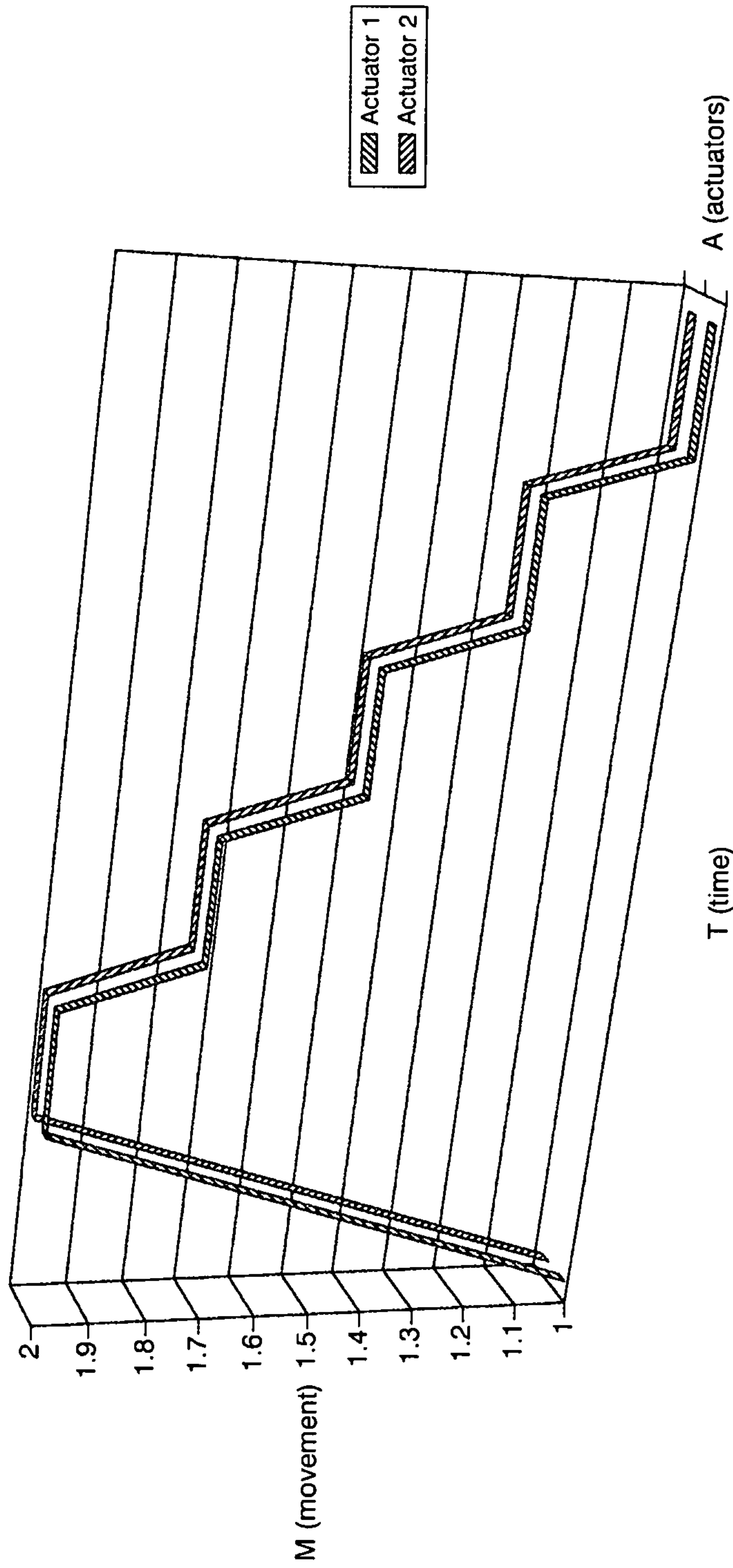


Fig. 16

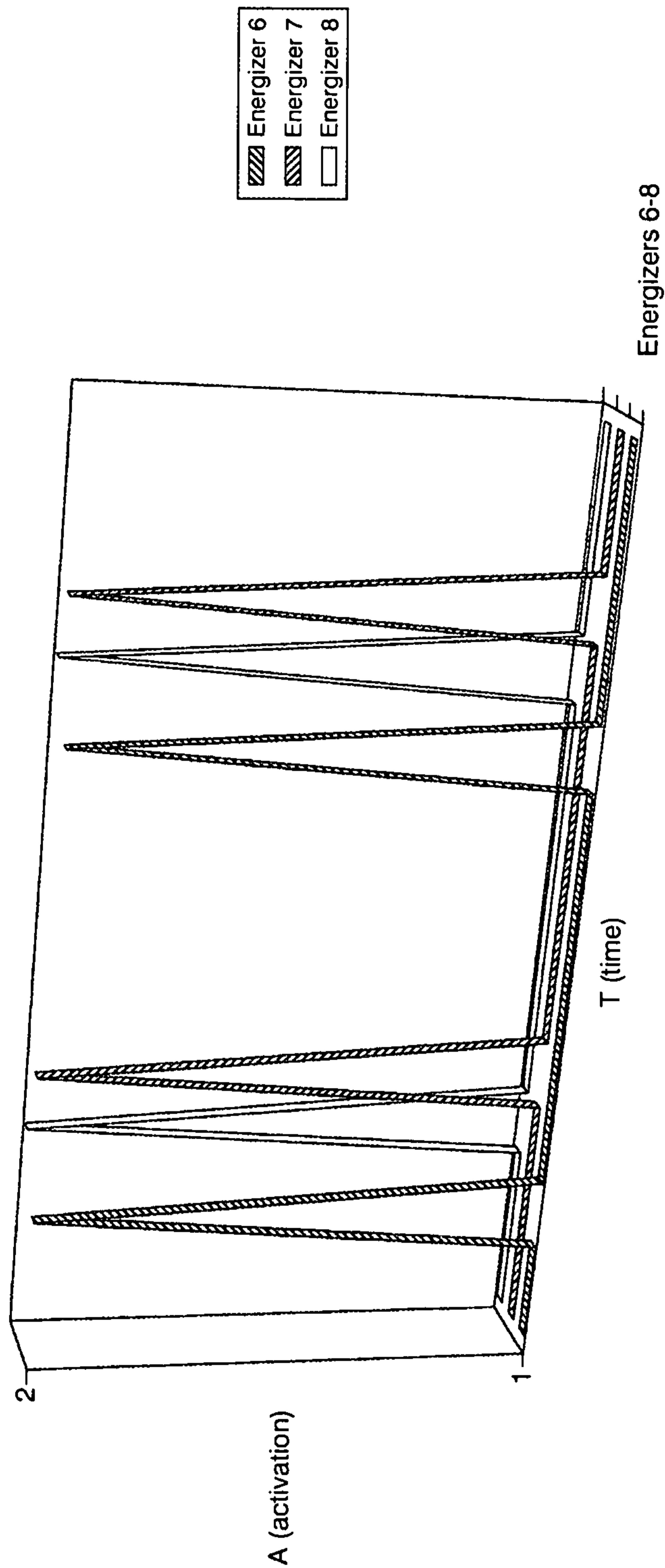


Fig. 17

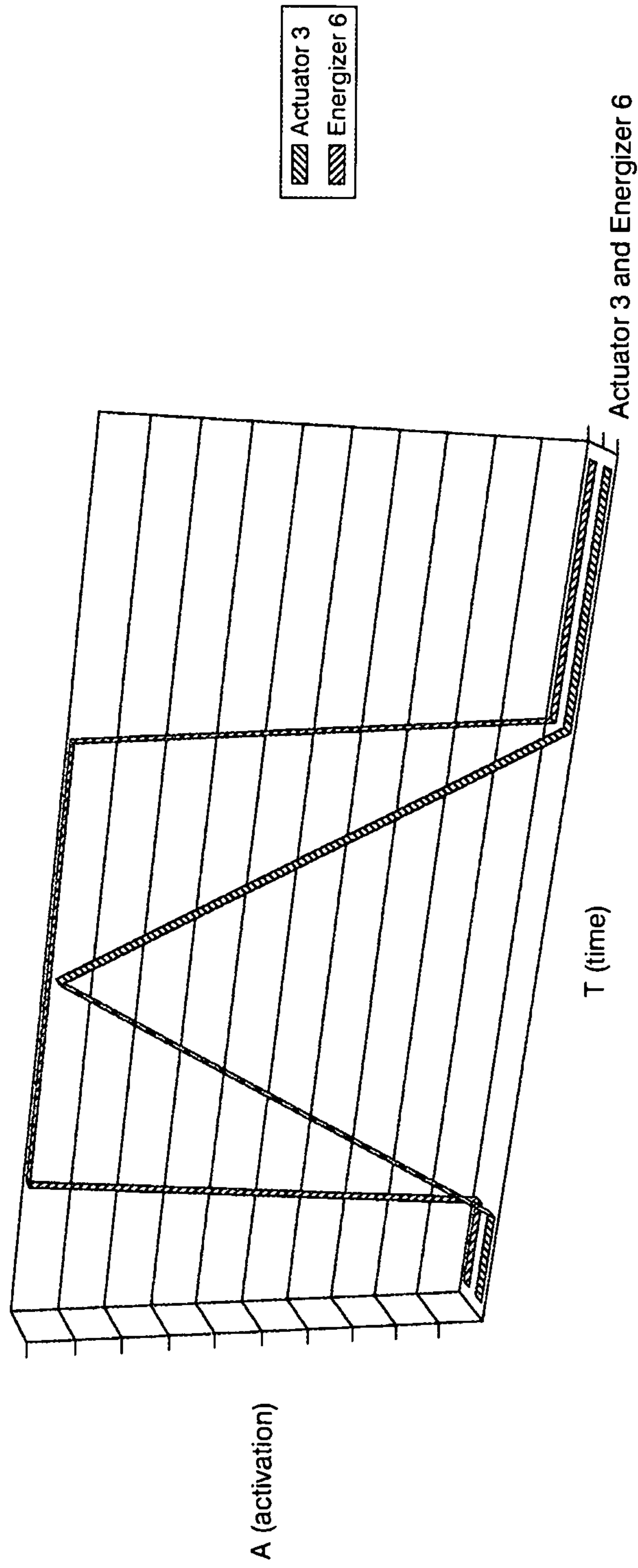


Fig. 18

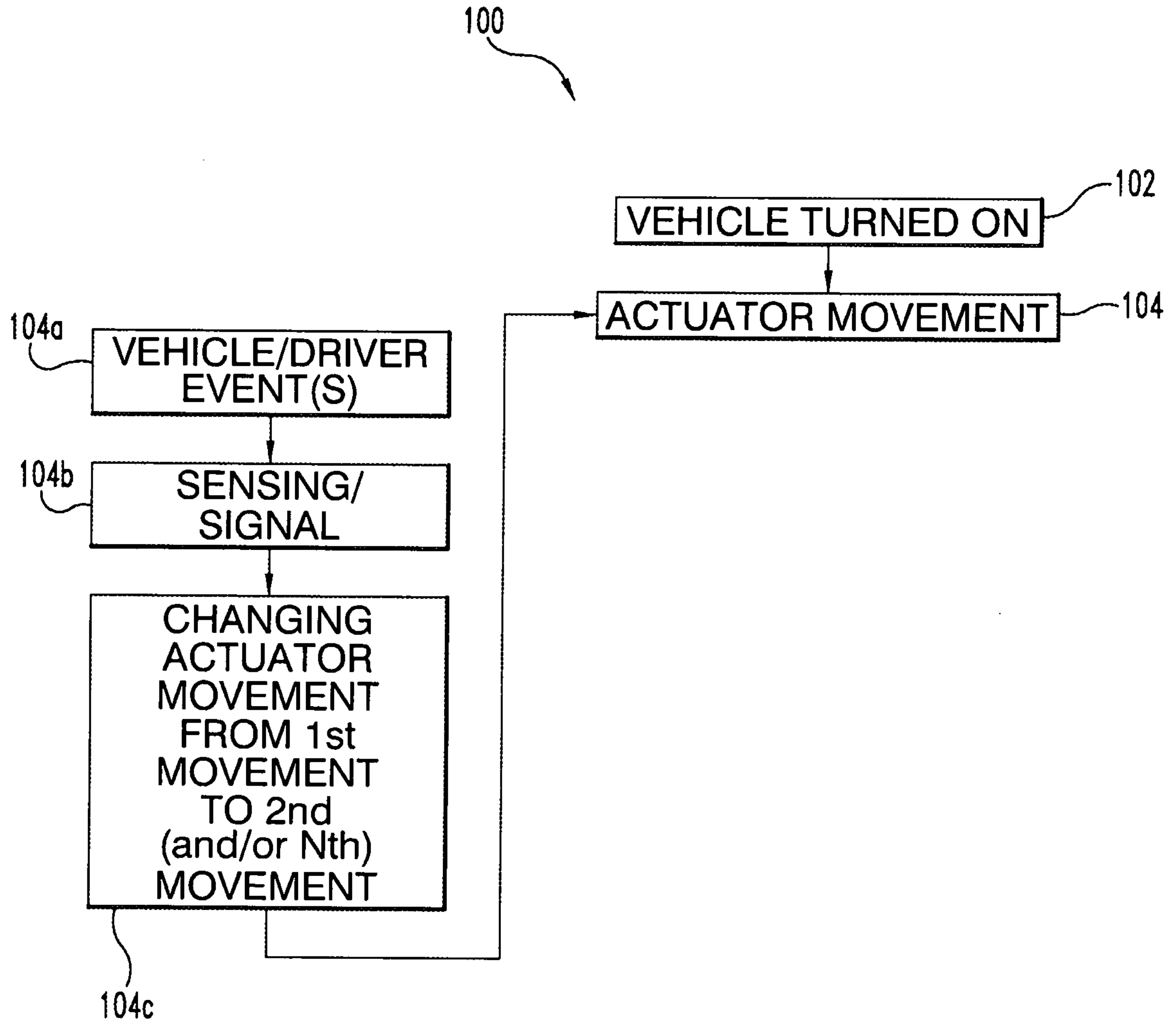


Fig. 19

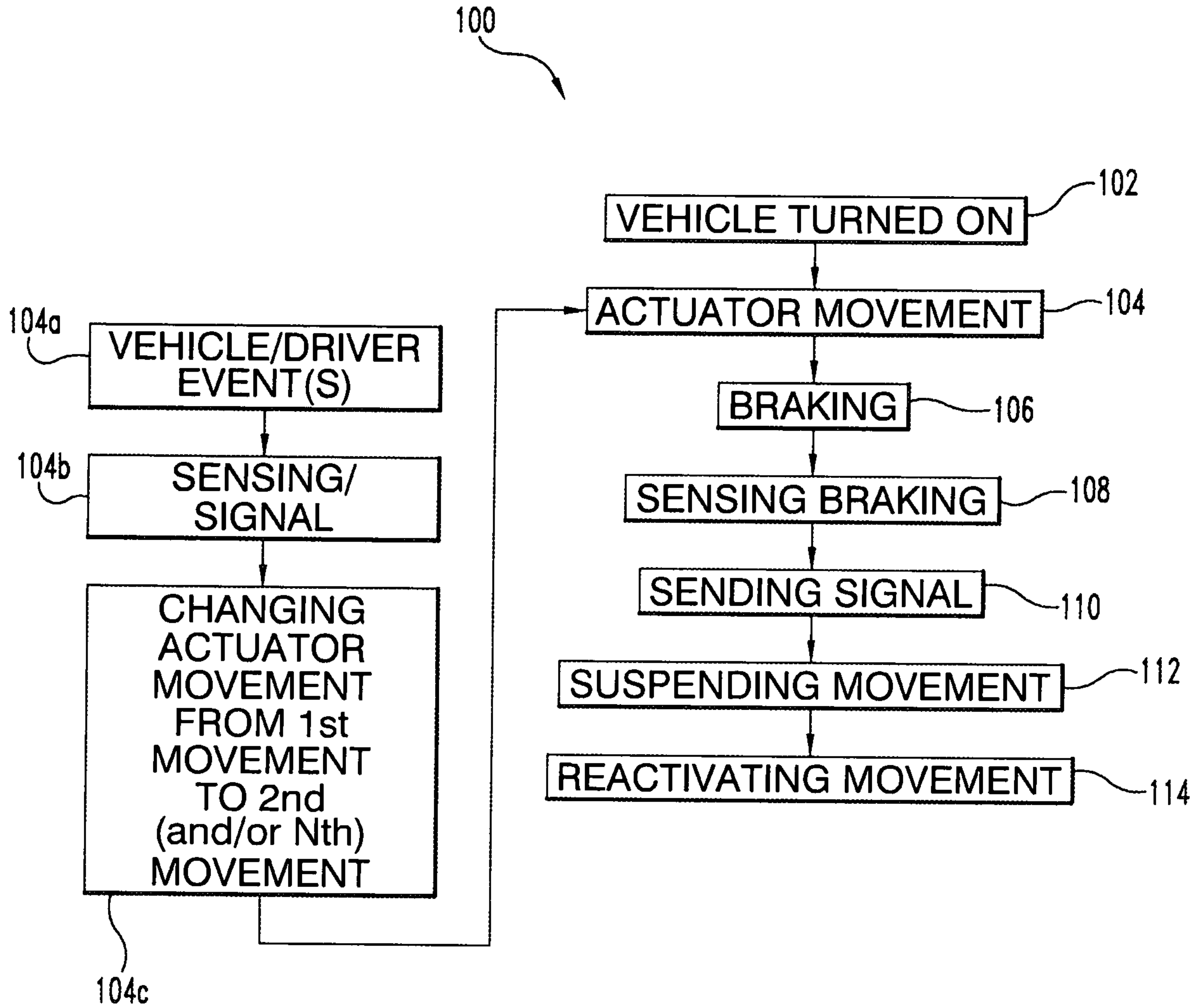


Fig. 20

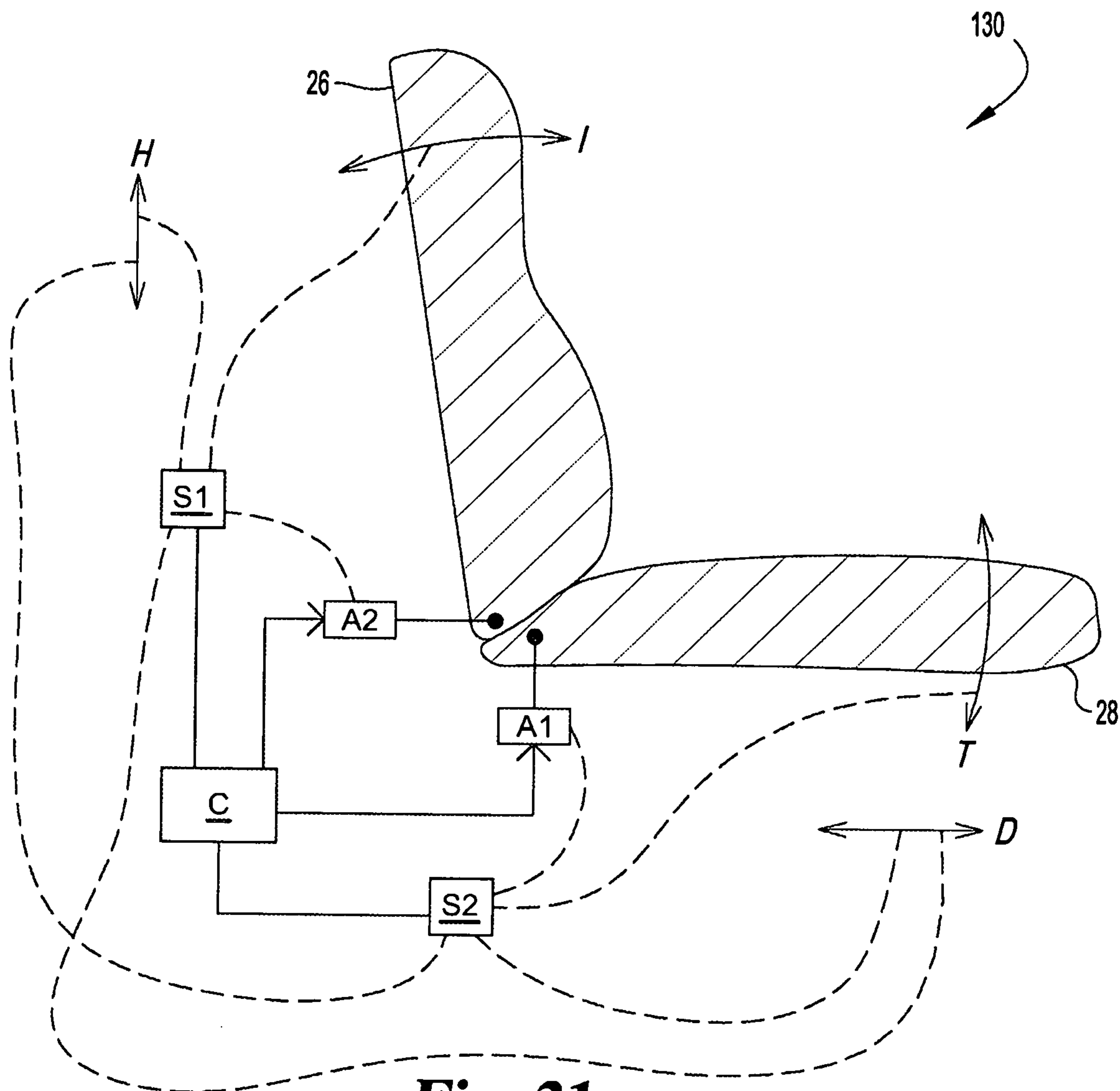


Fig. 21

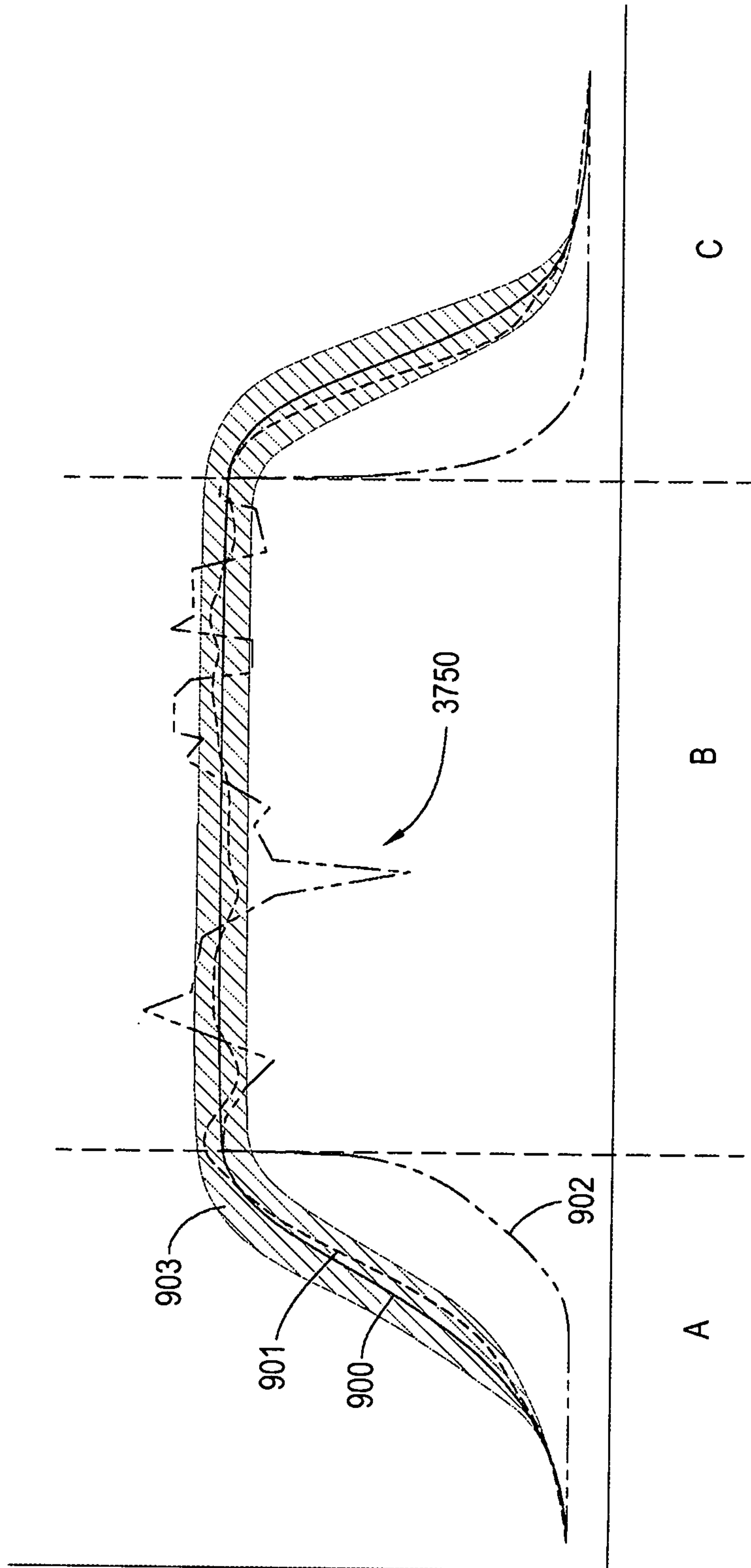


Fig. 22A

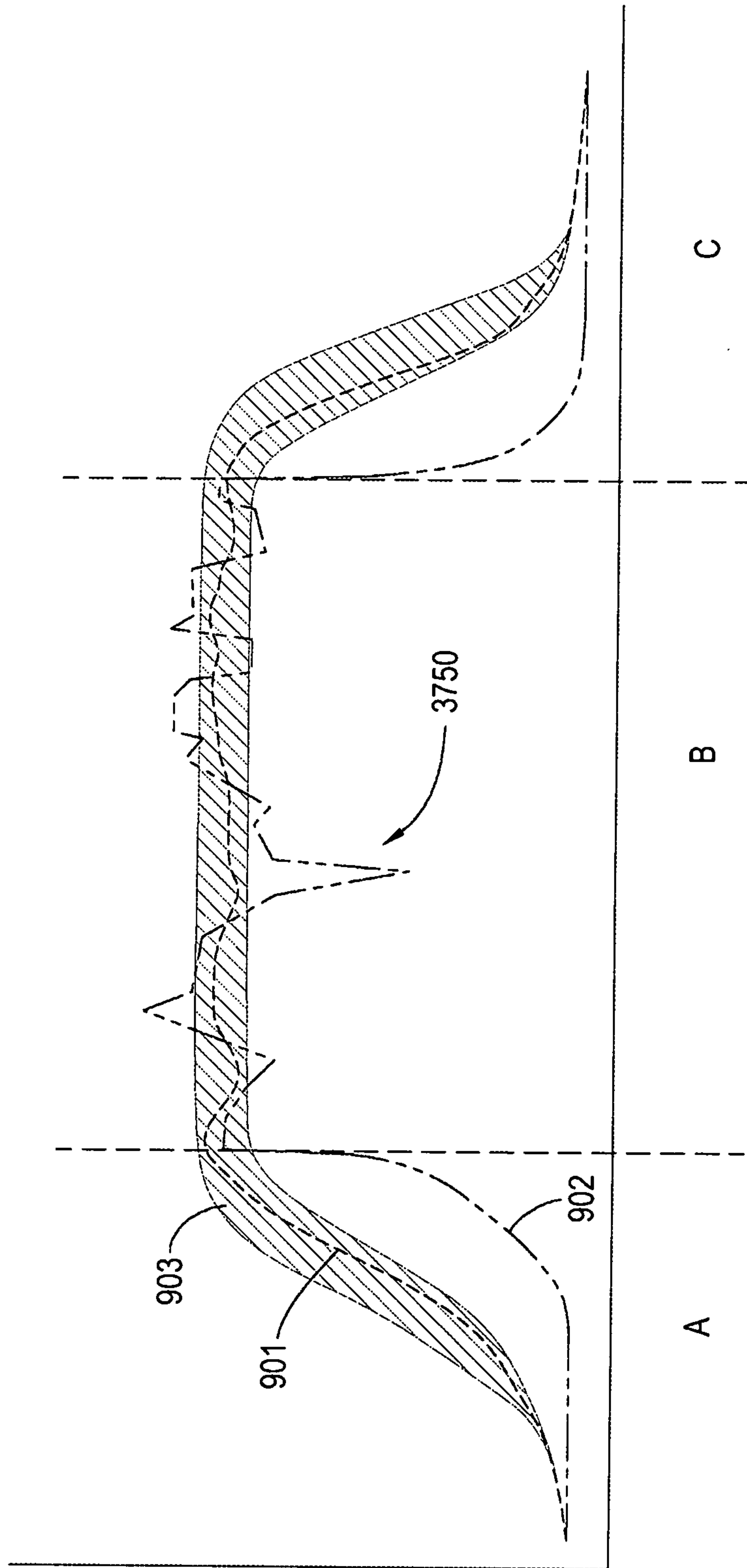


Fig. 22B

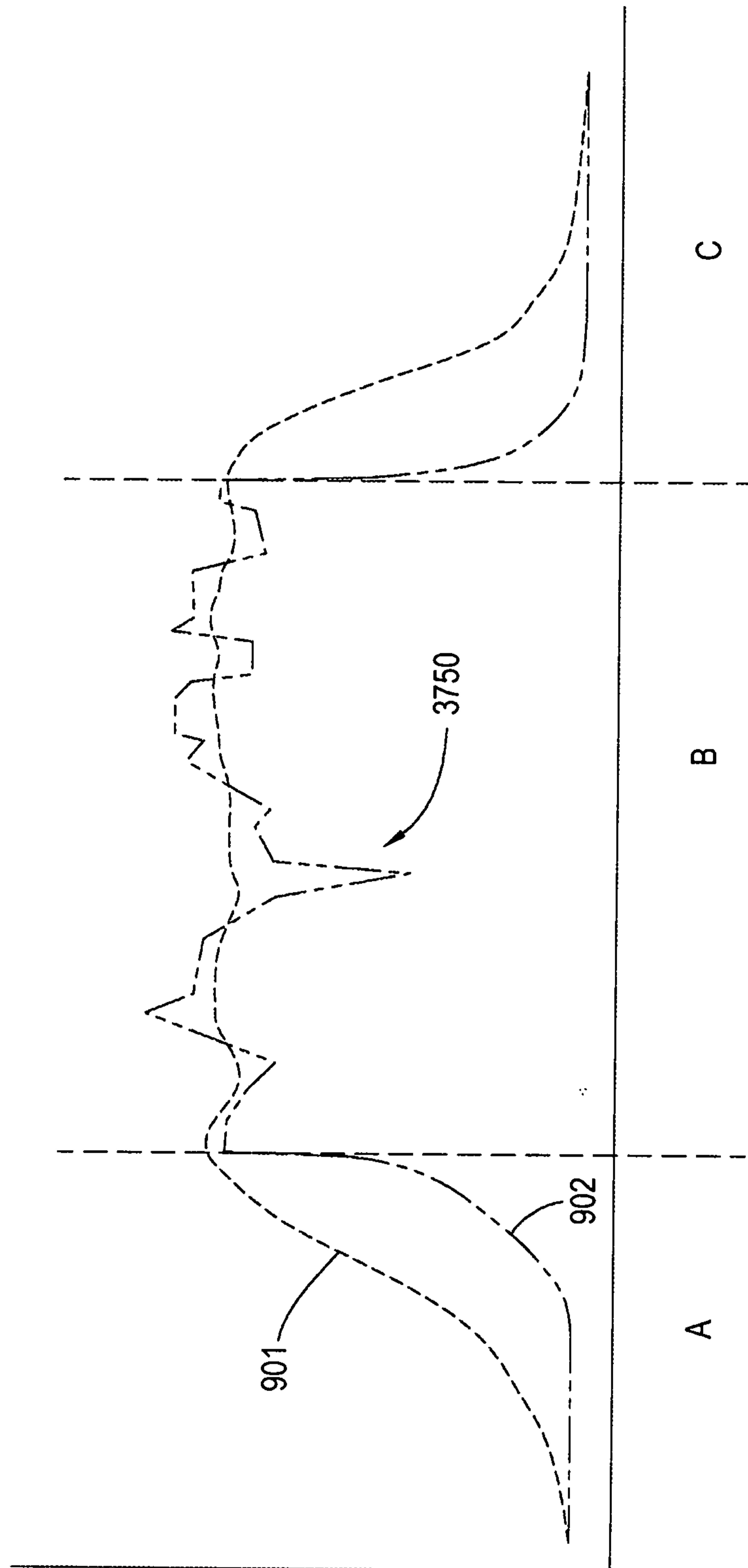


Fig. 22C

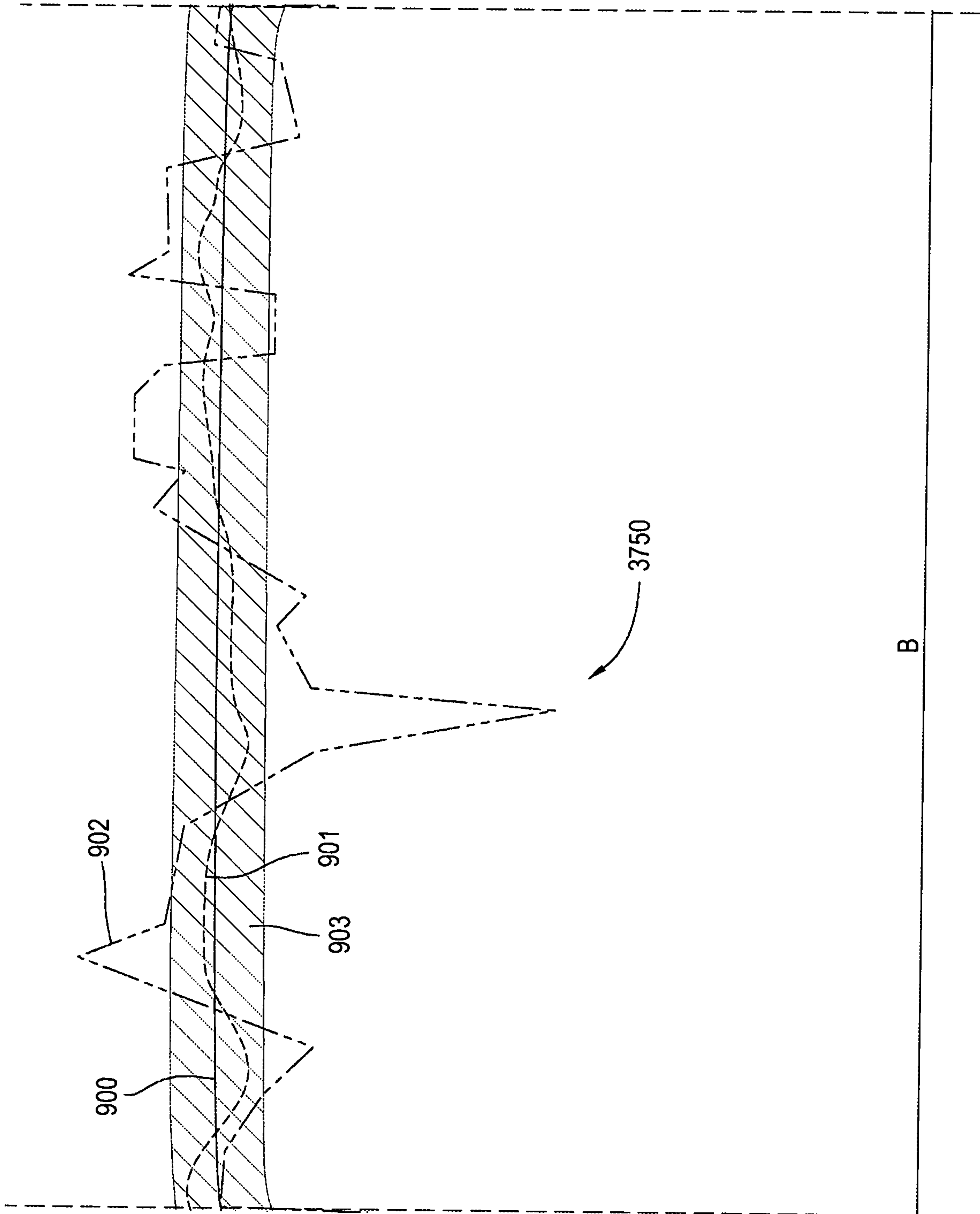


Fig. 22D

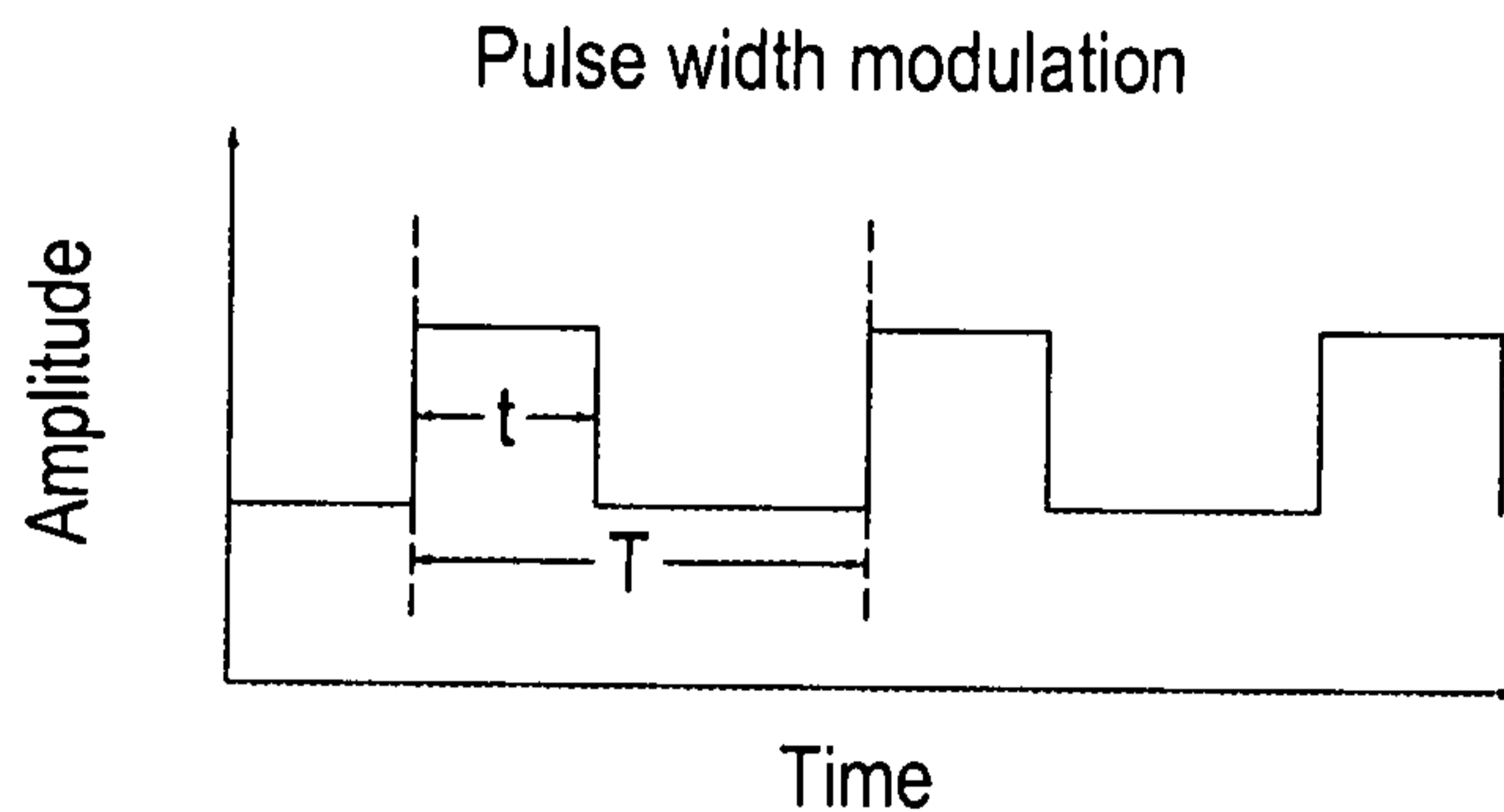


Fig. 23A

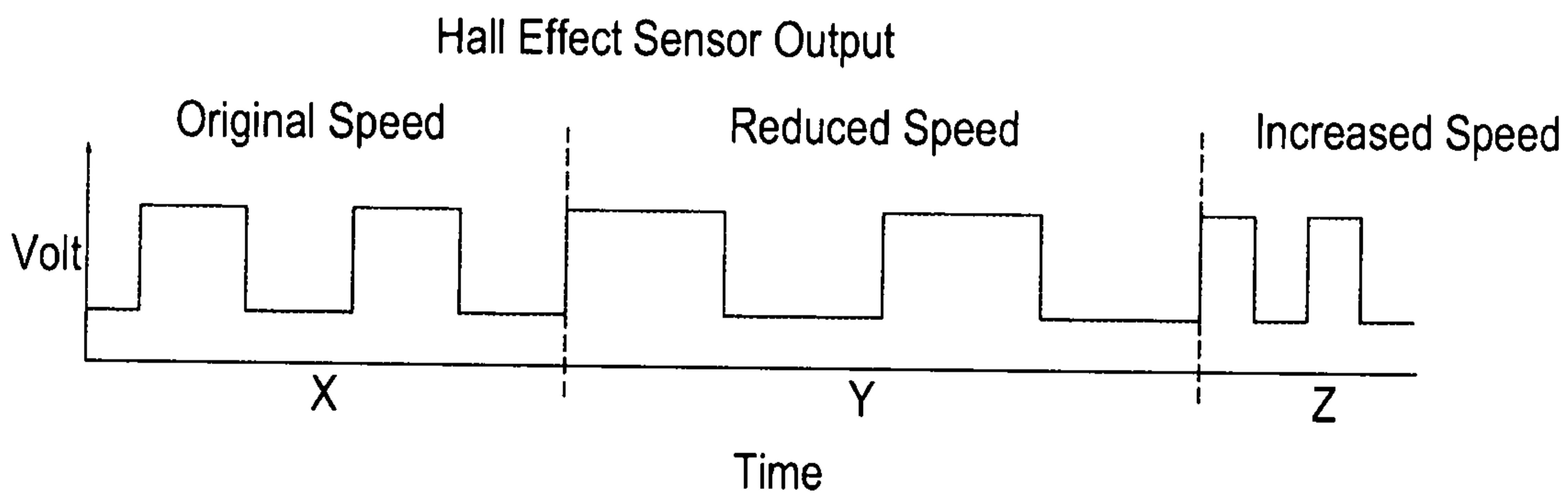


Fig. 23B

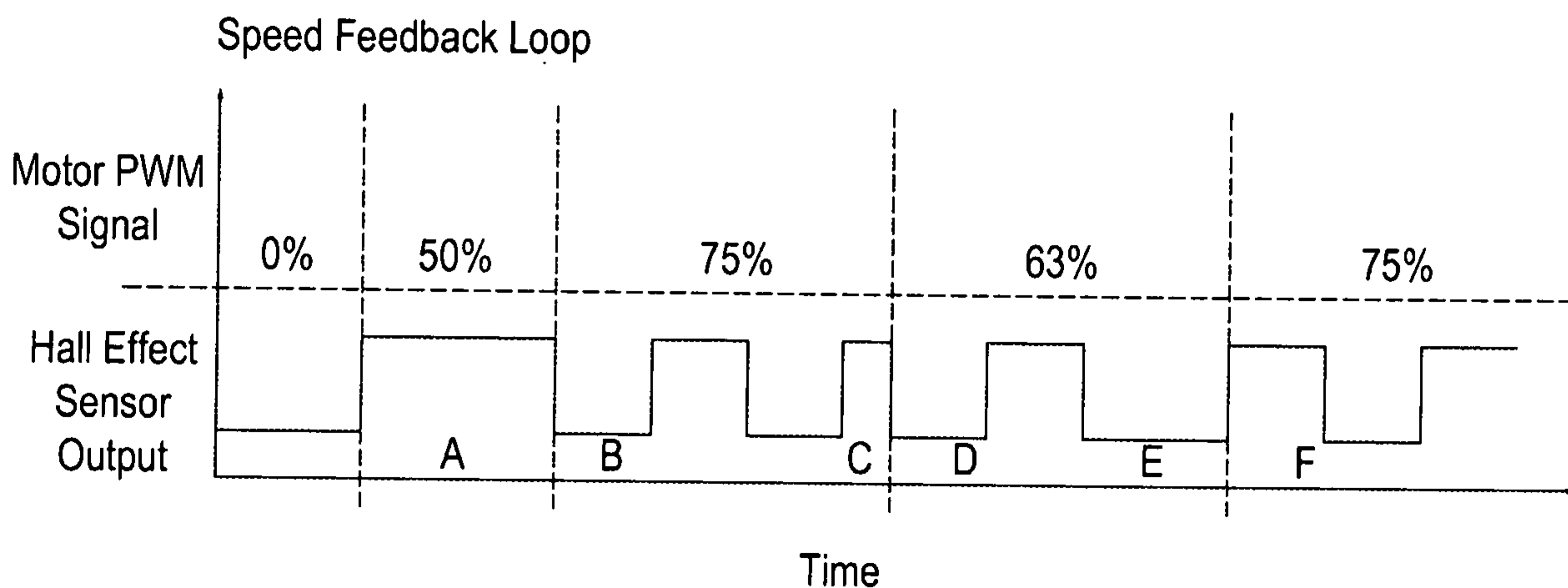


Fig. 23C

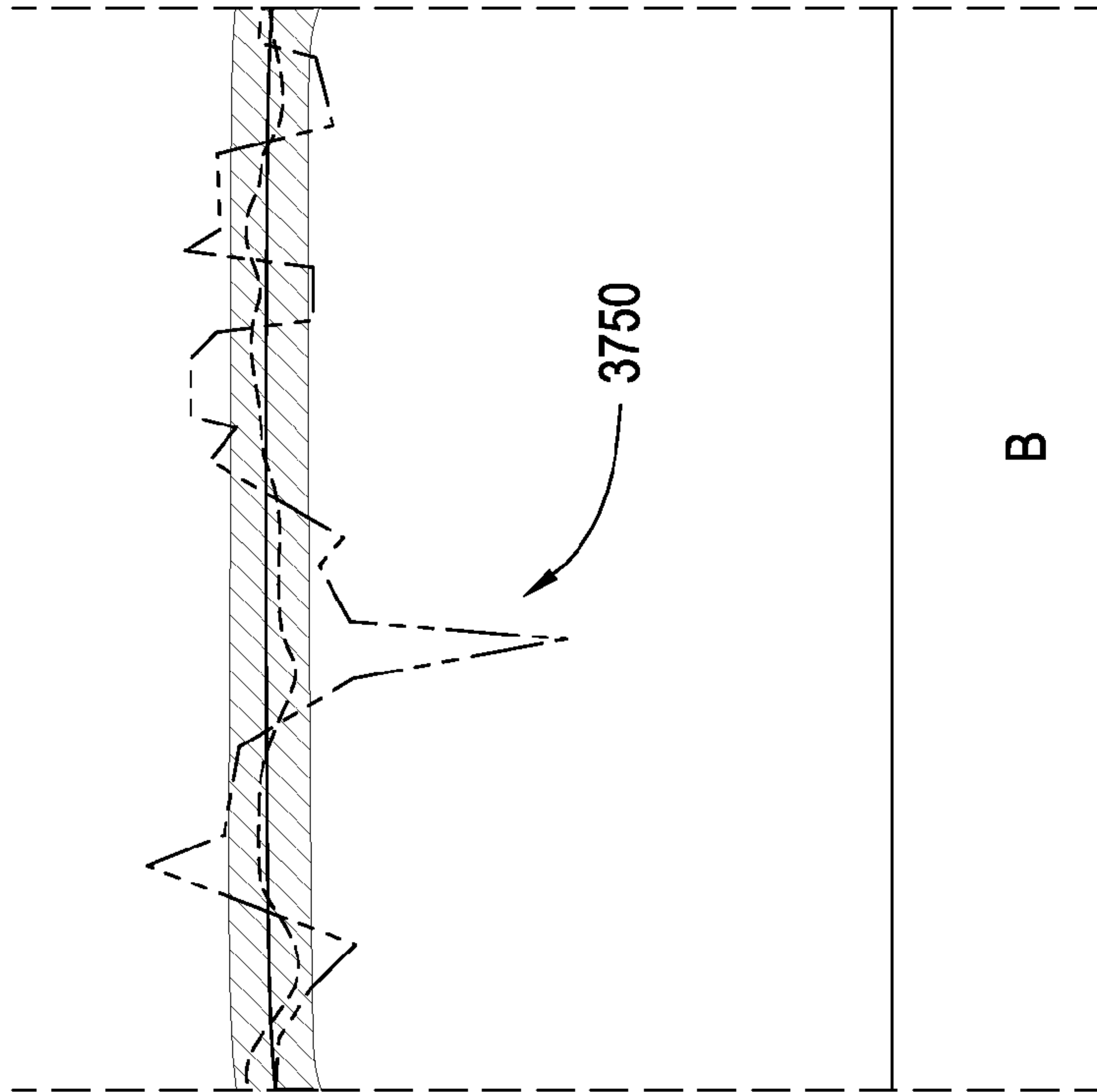
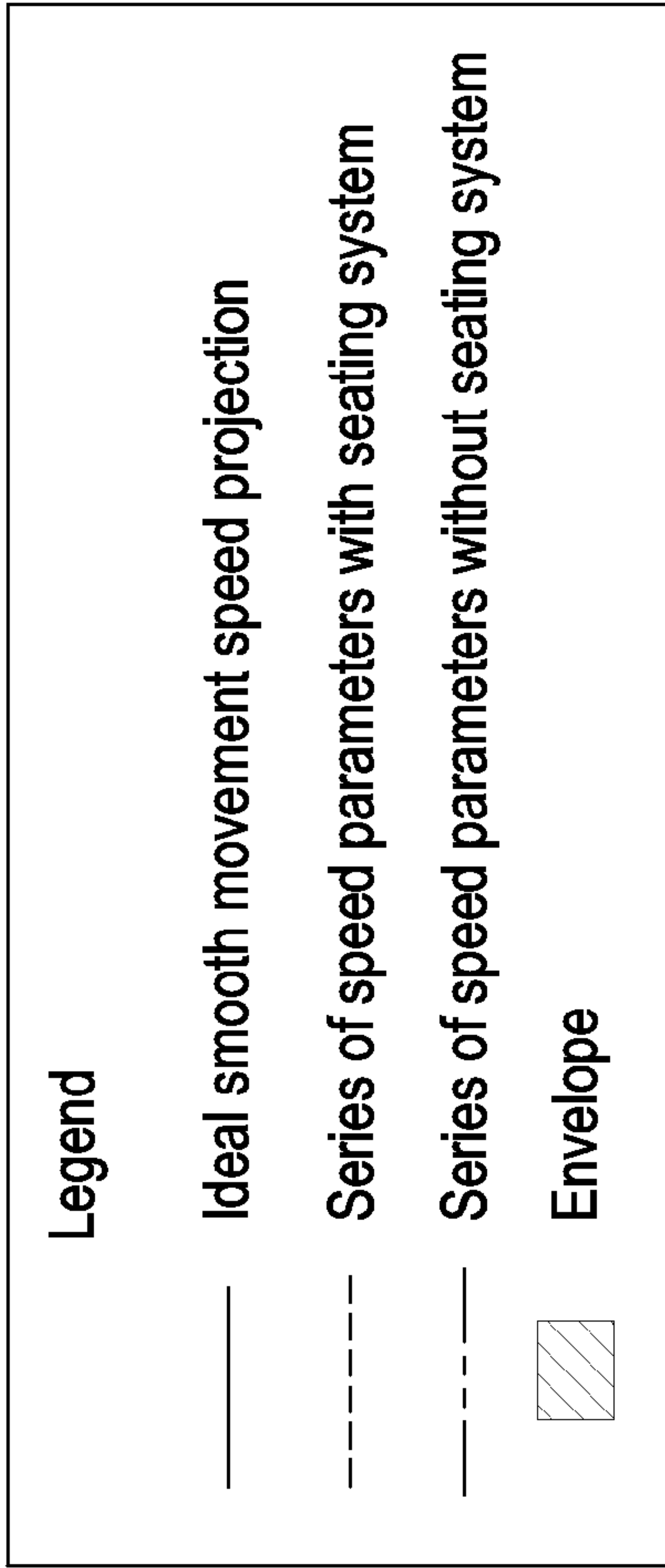


Fig. 23D

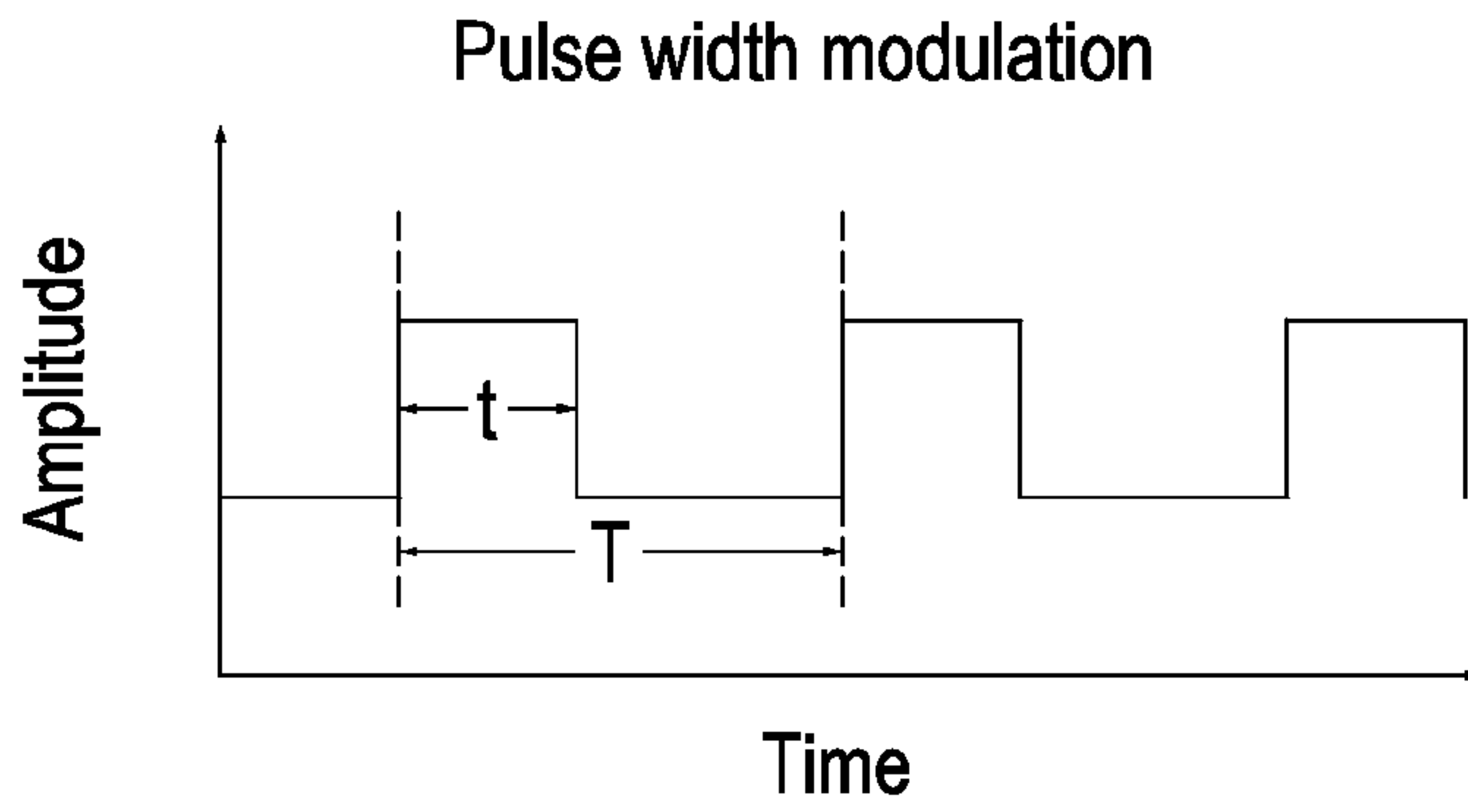


Fig. 24A

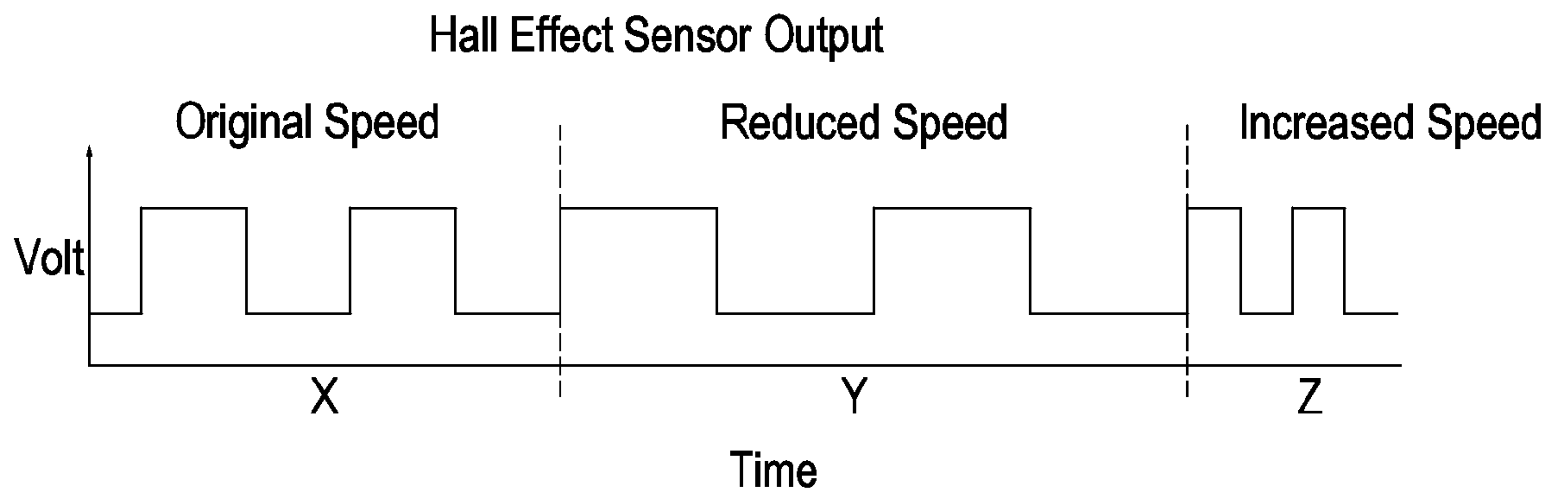


Fig. 24B

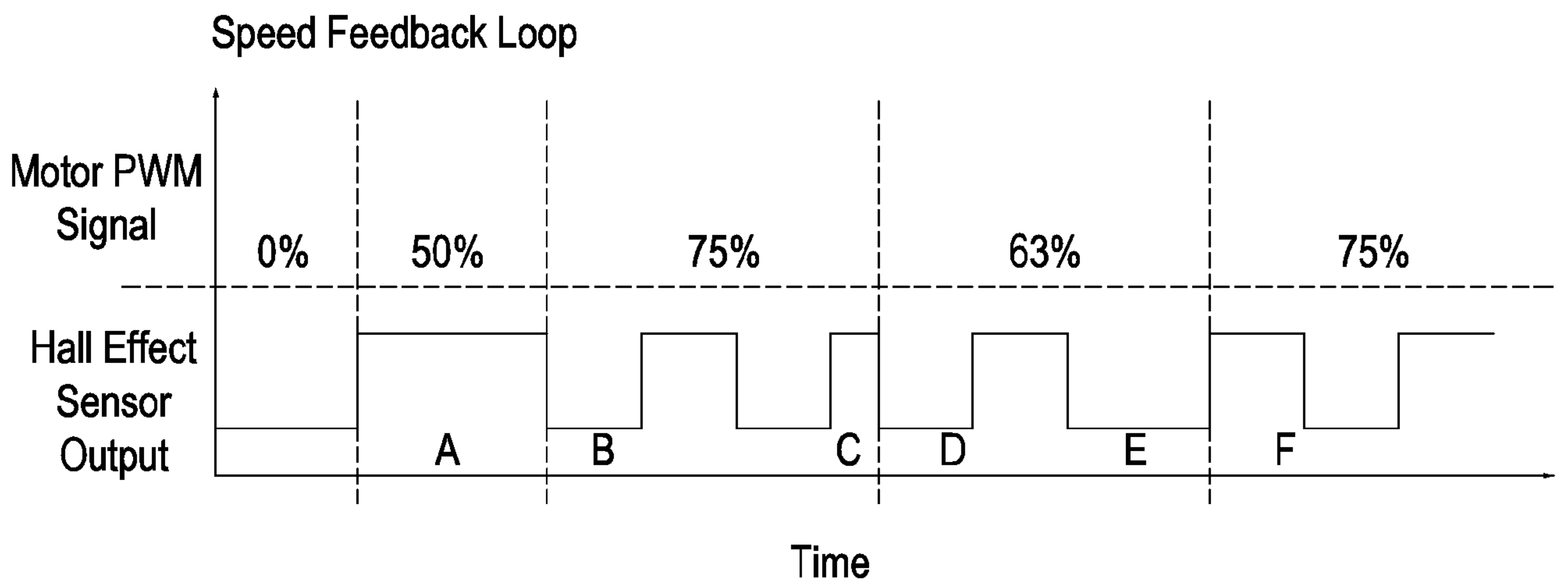


Fig. 24C

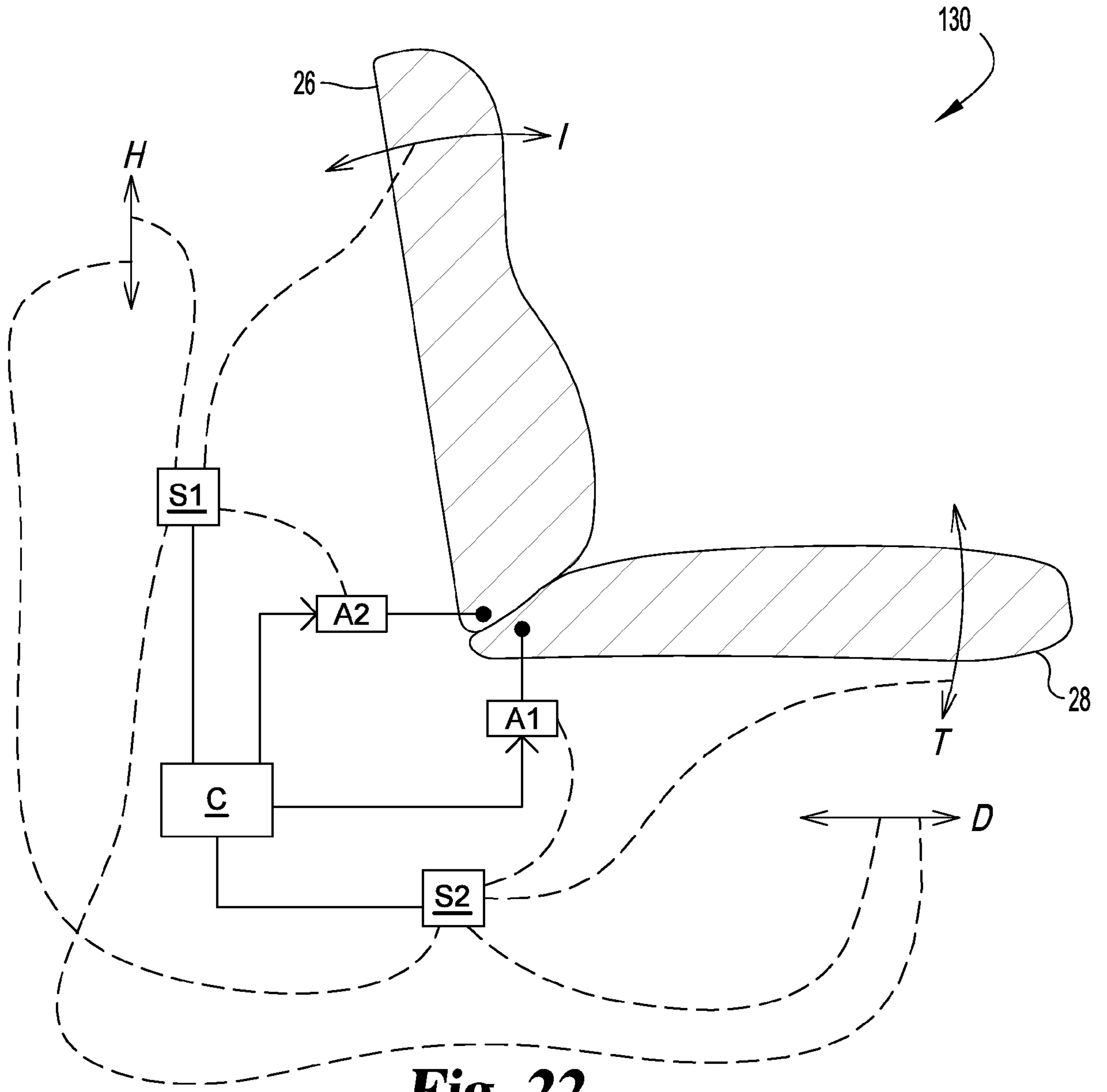


Fig. 22