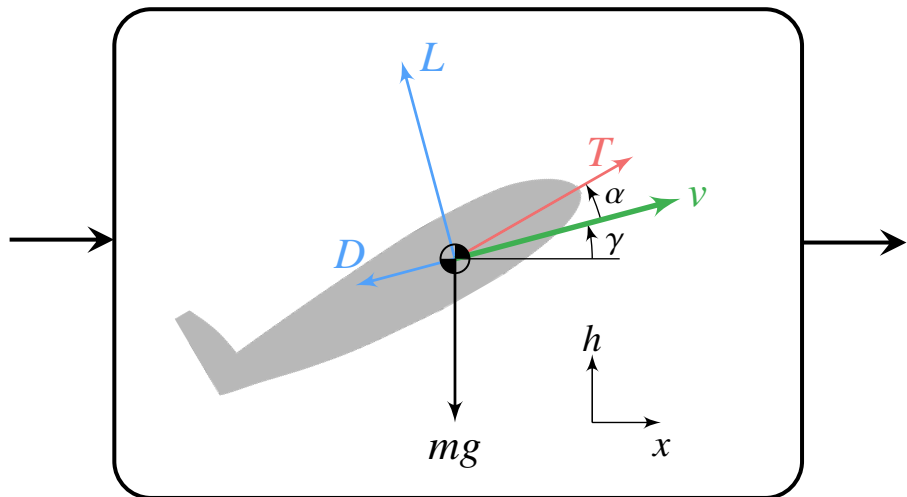
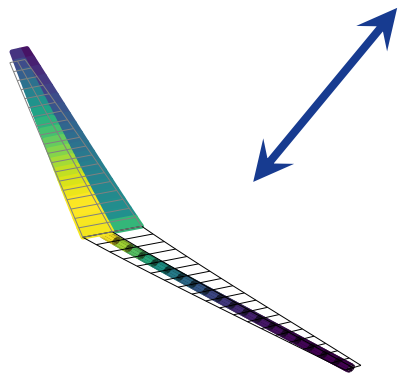


Dynamics model $\dot{\xi} = f(t, \xi, u, x_p)$

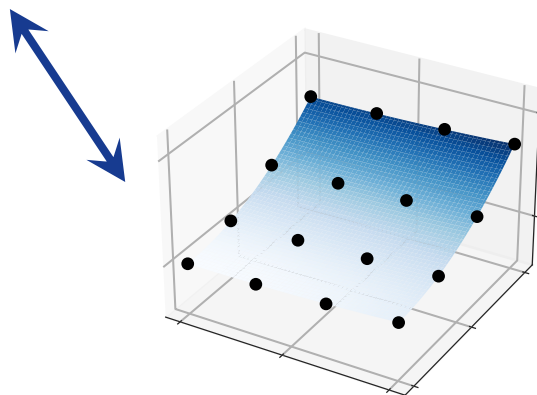


Re-trained for every
new vehicle design



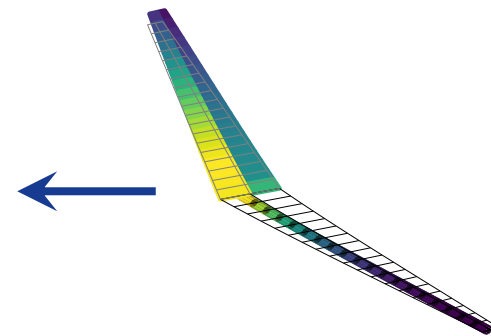
Disciplinary model

1. Direct coupling



Surrogate model

2. Surrogate-based coupling



Disciplinary model