# **MENU of SCORING BOXES**

#### While in lot

#### Driver Vehicle Readiness

* Rear in seat
* Adjust mirrors, head restraint
* Windows up, doors locked
* Belts on
* Headlights on

\***Precision Right Turns**

### At \_\_\_\_\_\_\_\_\_\_\_ turn right - Before

### FIND closed zone in target area

* Signal 100 ft. or 5 sec. ahead
* SOLVE reduce speed, check rear
* Side position 3 feet away
* CONTROL 45 º or 90 º search LFR

### At \_\_\_\_\_\_\_\_\_\_\_ turn right – During

* FIND open/closed/unstable zones
* Search to targetarea

###### Turn head then turn wheel

* Sees car to roadway w/ fringe
* Smooth gas @TP no roll felt

### At \_\_\_\_\_\_\_\_\_\_\_ turn right – After

# Search to target area

# Evaluate rear zone

# FIND open/closed/unstable zones

* SOLVE get best LP & speed control

# Maintain 4-sec following

### At \_\_\_\_\_\_\_\_\_\_\_ turn right – Moving

* Time arrival for open zones
* 45º search LFR
* Verbalize Front RP (over Rt. fender)

### Look into turn before turning

* Trail brake/maintain speed to TP

### At \_\_\_\_\_\_\_\_\_\_\_ turn right – Stopped

### Signal 5 sec. ahead

* Side position 3 feet away

### Forward position @ pedestrian zone

* Verbalize front limit RP

### @ Front limit search 90º LFR

### At \_\_\_\_\_\_\_\_\_turn right – Light

* FIND light in target area
* Check rear zone
* Time arrival for green
* Check for gap/hole in traffic
* Check LFR for open path

**Precision Left Turns**

### At \_\_\_\_\_\_\_\_\_\_\_ turn left – Before

* FIND closed zone in target area
* Signal 5 sec. ahead
* SOLVE reduce speed, check rear
* Front position @ pedestrian zone
* CONTROL 45º or 90º search LFR

### At \_\_\_\_\_\_\_\_\_\_\_ turn left – During

* FIND open/closed/unstable zones
* Search to targetarea

###### Turn head then turn wheel

* See car to roadway w/ fringe
* Smooth gas @TP no roll felt

### At \_\_\_\_\_\_\_\_\_\_\_ turn left – After

# Search to target area

# Evaluate rear zone

# FIND open/closed/unstable zones

# SOLVE get best LP & speed control

* Maintains 4-sec following

**At \_\_\_\_\_\_\_\_\_\_\_ turn left – Moving**

* Times arrival for open zones

### 45º search LFR

* Search to targetarea

### Turn head then turn wheel

### Trail brake/maintain speed to TP

**At \_\_\_\_\_\_\_\_\_\_\_ turn left – Stopped**

* Signal 5 sec. ahead
* Side position LP2 or LP1

### Staggered stop

* Legal stop @ pedestrian zone
* @ Front limit 90ºsearch LFR

**At \_\_\_\_\_\_\_\_\_\_\_ turn left – Light**

* FIND light in target area
* Check rear zone
* Time arrival for green
* Check for gap in traffic

### Check LFR for open path

### Approaching Intersections

### Before Turns or Going Straight

**2-Way Stop Controlled Intersection**

**No Stop Required**

At \_\_\_\_\_\_\_\_\_\_\_ turn right -Approach

* FIND closed/unstable zone
* SOLVE reduce speed
* SOLVE check rear zone
* CONTROL 45º Search LFR
* See clear path before gas

At \_\_\_\_\_\_\_\_\_\_\_ turn left - Approach

* FIND closed/unstable zone
* SOLVE reduce speed
* SOLVE check rear zone
* CONTROL 45º Search LFR
* See clear path before gas

Approach Intersection - Straight

* FIND closed zone
* SOLVE reduce speed
* SOLVE check rear zone
* CONTROL 45º Search LFR
* See clear path before gas

**Sign Controlled Inters: Stop Req.**

At \_\_\_\_\_\_\_\_\_\_\_ turn right -Approach

### FIND stop sign in target area

* SOLVE Reduce speed, check rear
* Smooth stop no pitch felt
* Forward position @ pedestrian zone
* CONTROL 90º LFR @ front limit

### At \_\_\_\_\_\_\_\_\_\_\_ turn left – Approach

### FIND stop sign in target area

* SOLVE Reduce speed, check rear
* Smooth stop no pitch felt
* Forward position @ pedestrian zone
* CONTROL 90º LFR @ front limit

**Approach Stop Sign - Straight**

### FIND stop sign in target area

* SOLVE Reduce speed, check rear
* Smooth stop no pitch felt
* Forward position @ pedestrian zone
* CONTROL 90º LFR @ front limit

##### 2-Way Controlled Intersection

##### Stop Required

At \_\_\_\_\_\_\_\_\_\_\_ turn right -Approach

* FIND stop sign in target area
* SOLVE reduce speed, check rear
* Smooth stop no pitch felt
* Front Position @ pedestrian zone
* CONTROL 90º LFR@ front limit

### At \_\_\_\_\_\_\_\_\_\_\_ turn left - Approach

* FIND stop sign in target area
* SOLVE reduce speed, check rear
* Staggered stop, front position
* CONTROL 90º LFR@ front limit
* See clear path before gas

##### 2-Way Controlled Intersection

##### Stop Required

**Approach 2-way stop- Straight**

* FIND stop sign in target area
* SOLVE reduce speed, check rear
* Smooth stop no pitch felt
* Front position @ pedestrian zone
* CONTROL 90º LFR@ front limit

###

### 4-way Stop

At \_\_\_\_\_\_\_\_\_\_\_ turn right -Approach

* FIND stop sign in target area
* SOLVE reduce speed, check rear
* Smooth stop no pitch felt
* Forward position @ ped zone
* See clear path before gas

### At \_\_\_\_\_\_\_\_\_\_\_ turn left - Approach

### FIND stop sign in target area

* SOLVE reduce speed, check rear
* Smooth stop no pitch felt
* Staggered stop, front position
* See clear path before gas

**Approach 4-way stop - Straight**

### FIND stop sign in target area

* SOLVE reduce speed, check rear
* Smooth stop no pitch felt
* Forward position @ pedestrian zone
* See clear path before gas

### Uncontrolled Intersection

### At \_\_\_\_\_\_\_\_\_\_\_ turn right-Approach

* FIND closed/unstable zone
* SOLVE check rear zone, apply brake
* CONTROL 45º search LFR
* See clear path before gas

**At \_\_\_\_\_\_\_\_\_\_\_ turn left-Approach**

* FIND closed/unstable zone
* SOLVE check rear zone, apply brake
* CONTROL 45º Search LFR
* Yield before entry
* See clear path before gas

**Straight across uncontrolled**

* FIND closed/unstable zone
* SOLVE check rear zone, apply brake
* CONTROL 45º Search LFR
* CONTROL yield before entry
* See clear path before gas

### Roundabout

* FIND closed/unstable zone
* SOLVE check rear, reduce speed
* CONTROL 45º search LFR
* CONTROL yield before entry
* See clear path before gas

**Yield Sign**

* FIND closed/unstable zone
* SOLVE check rear, reduce speed
* CONTROL 45º search LFR
* CONTROL yield before entry
* See clear path before gas

### Traffic Signal

**Approach Intersection** **- Straight**

* FIND unstable zone in target area
* SOLVE check rear, reduce speed
* SOLVE Time arrival for green
* CONTROL 45º or 90º search LFR
* CONTROL keep open side space

**Approach Intersection** **- Straight**

* FIND unstable zone in target area
* SOLVE check rear, reduce speed
* Know/apply point of no return
* Stop to see tires
* 2 second delay start

### At \_\_\_\_\_\_\_\_\_turn right – Light

* FIND unstable zone in target area
* Time arrival for green
* Check rear, reduce speed early
* Know/apply point of no return
* Check LFR for open path

### At \_\_\_\_\_\_\_\_\_\_\_ turn left – Before

* FIND light in target area
* Check rear zone
* Time arrival for green
* Check for gap in traffic
* Check LFR for open path

### Precision Lane Change

### In Heavy Traffic

##### When safe & legal, lane change right

* Evaluate zones, check blind spot
* Make/keep open side space
* Signal right & move to LP3
* Get a commitment
* Enters new lane in LP2

##### When safe & legal, lane change left

* Evaluate zones, check blind spot
* Make/keep open side space
* Signal right, move to LP2
* Get a commitment

##### Enter new lane in LP3

In Light Traffic

##### When safe & legal, lane change right

* Evaluate zones, check blind spot
* Make/keep open side space
* Signal right, move to LP3

### Make final blind spot check

* Enter new lane in LP2

##### When safe & legal, lane change left

* Evaluate zones, check blind spot
* Make/keep open side space
* Signal left, move to LP2

### Make final blind spot check

* Enter new lane in LP3

Into Turn Lane

### At \_\_\_\_\_\_\_\_\_\_\_ turn right

* FIND open/closed/unstable zones
* Signal right, move to LP3

### Make final blind spot check

* Reduce speed, check rear
* Enter new lane in LP2

**At \_\_\_\_\_\_\_\_\_\_\_ turn left**

* FIND open/closed/unstable zones
* Signal left, moves to LP2

### Makes final blind spot check

### 45º or 90º search LFR

* Enter new lane in LP3

**Approach/Search into Curves**

### Approach Right Curve

* Verbalize curve in target area
* Check all zones for options
* Reduce speed
* Get best lane position
* Open LF LP2-3-1 Closed LF LP1

### Negotiate sharp right curve

* Times arrival for open zones
* 45º search LFR
* Verbalize front RP (over Rt. fender)

### Look into turn before turning

* Trail brake/maintain speed to TP

**Approach Left Curve**

* Verbalize curve in target area?
* Check all zones for options
* Effective speed control
* Get best lane position
* Open RF LP3-1-1 ⬜ Closed RF LP1

Approach S-Curves Rt./Lt.

* See Curves in target area
* Check all zones for options
* Speed reduction, check rear
* LP2, LP3, LP1
* LP1, LP1, LP1

Approach S-Curves Lt./Rt.

* See curves in target area
* Check all zones for options
* Speed reduction, check rear
* LP1, LP1, LP1
* LP2, LP3, LP1

**Approach/Search over Hills**

**Approach Hill Crest**

* FIND closed zone in target area
* SOLVE check rear, best speed
* SOLVE approach in LP1
* CONTROL search over hill
* CONTROL best LP and speed

### Limited Access Highways

### Getting On

### At \_\_\_\_\_\_\_\_\_\_\_\_ Enter Freeway

* Check rear zone
* Keeps 4 seconds of space
* Slow speed on ramp
* Search for gap to enter
* Signal and check blind spot

**Getting Off**

**At \_\_\_\_\_\_\_\_\_\_\_\_ Exit Freeway**

* Plan ahead, search to target area
* Signal 5 seconds ahead
* Maintain speed to exit ramp
* Reduce speed on exit ramp
* Check rear zone

**Hill Parking**

### Beyond \_\_\_\_\_\_\_\_\_\_\_\_\_\_ park vehicle

* Check rear, signal
* Apply brake
* Verbalize right side limit Ref. Point
* Turn wheels
* Set parking brake

### Re-enter traffic

* Release parking brake
* Check mirrors, signal left
* Check for open gap/path
* Get best lane position
* Cancel Signal

**Back-in Angle Parking**

### Beyond \_\_\_\_\_\_\_\_\_\_\_\_\_\_ park vehicle

* Effective Communication
* Side position 3 feet away
* Shift to reverse, 360º search
* Back to pivot pint, turn wheel
* Use inching speed

**Un-parking**

* Release parking brake
* Check mirrors and signal
* Search for and open gap/path
* Get best lane position
* Cancel Signal

**Forward** **Angle Parking**

### Beyond \_\_\_\_\_\_\_\_\_\_\_\_\_\_ park vehicle

* Check rear, signal, apply brake
* Side position 6-8 away
* Target center of space
* Use inching speed
* Secure vehicle

**Un-park**

* Shift to reverse, 360º search
* Yield right of way
* Back to pivot point
* Check front swing
* Turn wheel from top down

**Backing Straight**

### Beyond \_\_\_\_\_\_\_\_\_\_\_\_\_\_ pull to the right, back alongside curb

* Exit flow of traffic
* Shift to reverse, 360º search
* Target to rear
* Accurate tracking
* Target rear, smooth stop

### Re-enter traffic

* Shift to drive
* Check mirrors, signal left
* Check for open gap/path
* Get best lane position
* Cancel Signal

**Backing Turn About**

### At \_\_\_\_\_\_\_\_\_\_ back around corner

* Side position 12 inches away
* Shift to reverse, 360º search
* Back to pivot point
* Turn wheel from top down
* Check left front swing

### At \_\_\_\_\_\_\_\_\_\_ back around corner

* Side position 12 inches away
* Shift to reverse, 360º search
* Back to pivot point
* Yield before entering crosswalk
* Yield before entering street

### At \_\_\_\_\_\_\_\_\_\_ back into alleyway

* Side position 12 inches away
* Shift to reverse, 360º search
* Back to pivot point
* Turn wheel from top down
* Check left front swing

**Back-in Perpendicular Parking**

**Back into perpendicular space Rt.**

* Effective Communication
* Side position 3 feet away
* 45º target left, go forward/left
* Evaluate alignment to space
* Back to pivot point, turn wheel

**Un-park**

* Effective Communication
* 180º search
* Yield right of way
* Pull to forward position
* Search and turn wheel

**Parallel Parking**

### Parallel Park – communication

* Rear zone control, signal Rt.
* Reduce speed, brake lights
* Side position 3 feet away
* Line up pivot point
* Reverse lights

**On \_\_\_\_\_\_\_\_\_ parallel park**

* Back to rear pivot point
* Check left-front corner swing
* Creep and turn wheel fully
* Move car to 45º angle
* Creep and time to clear front car

### Re-enter traffic

* Release parking brake
* Check mirrors, signal left
* Check for open gap/path
* Get best lane position
* Cancel Signal

**Speed Zones** (various examples)

* Unposted speed 25
* School speed zone 20
* Maintain posted speed 45
* Speed too fast/slow

**Following Time and Space**

**Following Time**

* FIND traffic in target area
* Adjust speed/front closure rate
* Keep 4 seconds of time
* Respond to communications
* Verbalize benefits of 4 seconds

**Static Space Management**

# **Managing Time & Space**

# Search to target area

# FIND closed/unstable zones

# Maintains 4-sec following

* Maintains open side zones
* Courteous, not competitive

**Managing Time & Space**

# FIND closed/unstable zones

* SOLVE check related zones
* SOLVE time arrival for open zones
* CONTROL 4 sec. zone
* Courteous, not competitive

**Dynamic Space Management**

**Managing Time & Space**

* ⬜ ⬜ ⬜ ⬜ FIND zone conditions
* ⬜ ⬜ ⬜ ⬜ SOLVE check other zones
* ⬜ ⬜ ⬜ ⬜ SOLVE best speed, & LP
* ⬜ ⬜ ⬜ ⬜ SOLVE Communicates
* ⬜ ⬜ ⬜ ⬜ CONTROL 4 sec. Zone

**Basic Skills**

### Basic Skills

* Pivot on heel from brake to gas
* Steering control @ 9 & 3 or 8 & 4
* HOH or P-Pull for right turns
* P-Pull for curves and left turns
* Shift efficiently

**This document is called a “Menu” because it contains many of the maneuvers that you will need to document in your final route.**

**(GIF Codes Below)**

**Grounds for Immediate Failure – GIF Codes**

* G1 - Crash/Instructor intervention to prevent crash
* G2 - Ignores a command for required maneuver
* G3 - Drives or backs over a curb/sidewalk - hazard for pedestrian
* G4 - Improper action/serious traffic hazard

**Student commits any of the following dangerous actions:**

* G5a - Passes vehicle stopped at a crosswalk yielding to a pedestrian
* G5a - Passes school bus stopped with red lights flashing
* G5b - Makes, or starts to make, a turn from the wrong lane in dangerous conditions
* G5c - Runs through, or must be stopped from running a red light or stop sign

By the final drive, an instructor will rarely, if ever need to engage the use of a GIF code. These are provided merely for a documentation tool for when/if the situation arises.