

CLAIMS

1.- A driving system (1) for two vehicles positioned one behind the other, said driving system (1) comprises a first vehicle (2) and a second vehicle (3), the two
5 vehicles (2, 3) comprise communication means (4a, 4b) and the first vehicle (2) comprises remote driving means (6a) as well as acquisition means (5) configured to acquire visual and operating information of the first vehicle (2), this information is sent by the communication means (4a,
10 4b) to the second vehicle (3), the latter comprises viewing means (7) configured to view said information, a driver (8) being positioned in the second vehicle (3) and being able to control the remote driving means (6a, 6b) of the first vehicle (2) as a result of said information,

15 characterised in that the second vehicle (3) is adapted to follow the first vehicle (2) and in that the second vehicle (3) comprises remote driving means (6b), the second vehicle (3) being driven automatically based on the movements of the first vehicle (2).

20 2.- The system according to claim 1, characterised in that the communication means (4a, 4b) comprise radio devices or a wired network.

3.- The system according to claims 1 or 2, characterised in that the acquisition means (5) comprise at
25 least one of the following means: video cameras, distance

sensors or operation sensors of the vehicle (2).

4. The system according to one of the preceding claims, characterised in that the viewing means (7) comprise at least one monitor configured to view the information
5 acquired by the acquisition means (5).

5.- The system according to one of the preceding claims, characterised in that the second vehicle (3) comprises manual driving means which, if activated, take priority over the automatic driving of the second vehicle.

10 6.- The system according to one of the preceding claims, characterised in that the two vehicles comprise safety means configured to stop the two vehicles (2, 3) if one of the acquisition means (5), the viewing means (7), the remote driving means (6a, 6b) or the communication
15 means (4a, 4b) is faulty.

7.- The system according to one of claims 1 to 6, characterised in that said automatic driving based on the movements of the first vehicle (2) is implemented as a result of a time offset between the first vehicle and the
20 second vehicle.