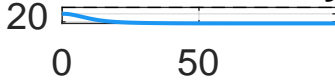
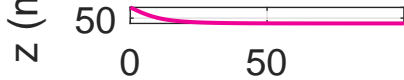


v (m/s)

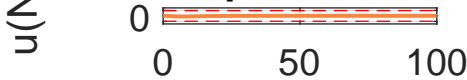
State - Velocity



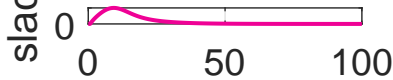
State - Distance to lead vehicle



Control Input - Wheel Force

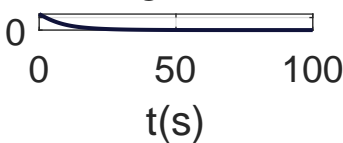


Slack variable



$CBF(h(x))$

CBF



$CLF(V(x))$

CLF

