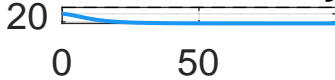


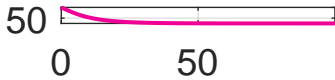
v (m/s)

State - Velocity



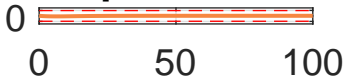
z (m)

State - Distance to lead vehicle



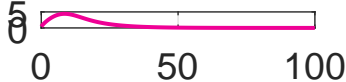
Control Input - Wheel Force

u (N)



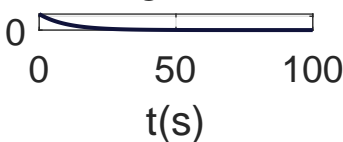
Slack variable

slack



$h(x)$

CBF



$V(x)$

CLF

