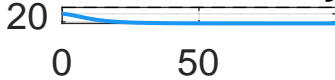


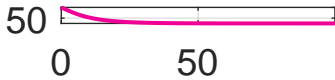
v (m/s)

State - Velocity

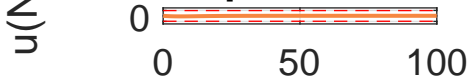


z (m)

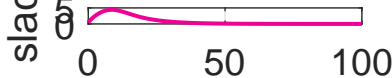
State - Distance to lead vehicle



Control Input - Wheel Force

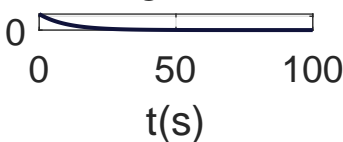


Slack variable



$h(x)$

CBF



$V(x)$

CLF

