```
{d = d0; v = v0; ed = ed0; ev = ev0;}
Speed Control
                                                              Spacing Control
                                            [ed < 10 + 2*ev]
du:
                                                               du:
d dot = -v+vI:
                                                               d dot = -v+vI:
v dot = 2*vl - v - ev:
                                                               v dot = 2^*vI - v - ev - 0.25^*(10 + 2^*ev - ed);
                                                               ed dot = vl - ev + 10*(d + nrad - ed);
ed dot = vl - ev + 10*(d + nrad - ed);
ev dot = 2*vl + v - 3*ev
                                                               ev dot = 2*vl + v - 3*ev
                                                               + 0.5*(2*theta*ngps + 2*(1-theta)*nenc) - 0.25*(10 + 2*ev - ed);
+ 0.5*(2*theta*ngps + 2*(1-theta)*nenc);
d out = d;
                                                               d out = d:
v out = v;
                                                               v out = v:
                                          [ed >= 10 + 2*ev] ed_out = ed;
ed out = ed;
                                                               ev out = ev;
ev out = ev:
```