Signal Type		Signal Name	Signal Location	Signal Unit	Signal Description
ACC	Host_Long_Accel_mpss	Host_Long_Accel_mpss	det_host_veh_state	m/s2	Fused IMU host vehicle acceleration and ActVehAccel
	Host_Speed_mps	Host_Speed_mps	det_host_veh_state	m/s	Filtered host vehicle speed
	ACCDrvrSeltedSpd_mps	ACCDrvrSeltedSpd_mps	HMI_GM	m/s	Driver selected host vehicle ACC speed
	Map_Speed	Map_Speed	from Perception/Localization	m/s	Speed limit derived from map
	TSR_Speed	TSR_Speed	from Perception/Localization	m/s	Traffic sign speed
	Allowed_Speed	Allowed_Speed	from Controls	m/s	Final decision speed
	ACC_Target_Present	ACC_Target_Present	Lead_Vehicle_State	bool	Target vehicle present or not
	ACC_Target_Speed_mps	ACC_Target_Speed_mps	Lead_Vehicle_State	m/s	Target vehicle speed
	ACCRange	ACCRange	Lead_Vehicle_State	m	Target vehicle distance from host vehicle
	ACCRangeRate	ACCRangeRate	Lead_Vehicle_State	m/s	Rate of distance change between host and target vehicle
	ACCA_State	ACCA_State	HWP_Supervisor	num 0-4	Only ACCA_State = 3 means ACC engaged
LC	LV_Steer_angle_final	LV_Steer_angle_final	HWP_Lane_Centering	rad	final road wheel angle
	RxMotionCtrlLatAccel	RxMotionCtrlLatAccel	FlexRay	m/s2	Lateral acceleration
	IMUYawRtPri	IMUYawRtPri	Veh_Rx_Translator	degree/s	filtered Yaw rate
	Host_Speed_mps	Host_Speed_mps	det_host_veh_state	m/s	Filtered host vehicle speed
	Curvature	A[2]	Lateral controller LQR _MPC	1/m	2*A[2]
	xhatout	[Larteral Error, Lateral Error rate, Heading Error, Heading Error rate]	EKF	[m, m/s, rad, rad/s]	EKF estimated state, we need xhatout[1]
	Lateral distance	A[0]	Lateral controller LQR _MPC	m	A[0]
Vehicle State	AUTO/Manual	HP_Mode	HP_Mode_Supervisor	num 0-7	Only HP_Mode = 3 means Vehicle engaged