Ego Vehicle

$t = t_{n-2}$   $t = t_{n-1}$   $t = t_n$

the node

$d_{node,i,t}$

state of the surrounding vehicle $i$ :

$$\mathbf{S_i} = (\mathbf{d_{node,i}}, \mathbf{v_i}, \mathbf{a_i})$$

$$\mathbf{TTC} = \frac{\mathbf{d_{node,i}}}{\mathbf{v_i}}$$

$t = t_n$

$t = t_{n-1}$

$t = t_{n-2}$

Surrounding Vehicle