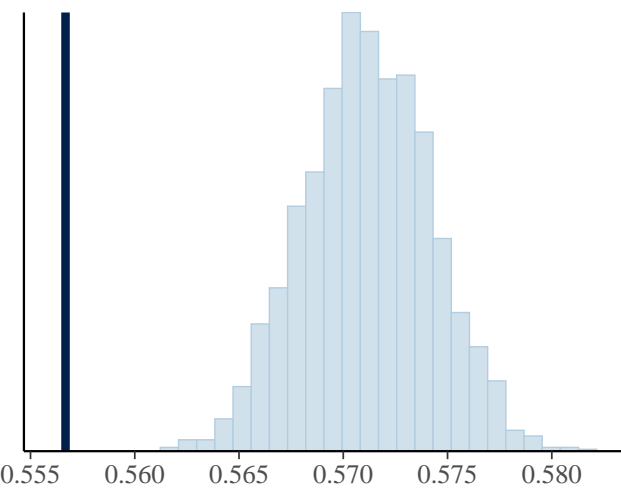
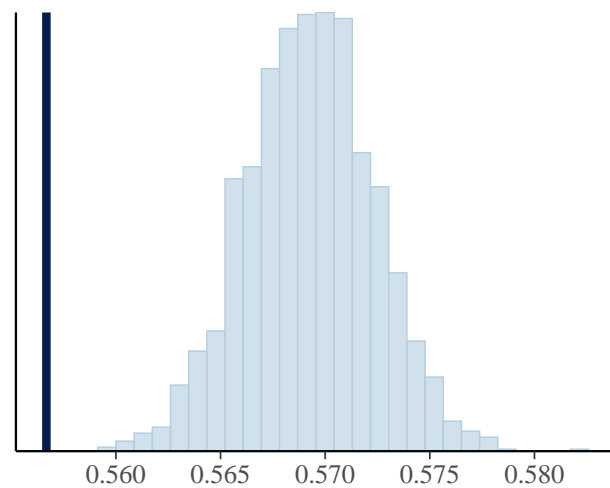


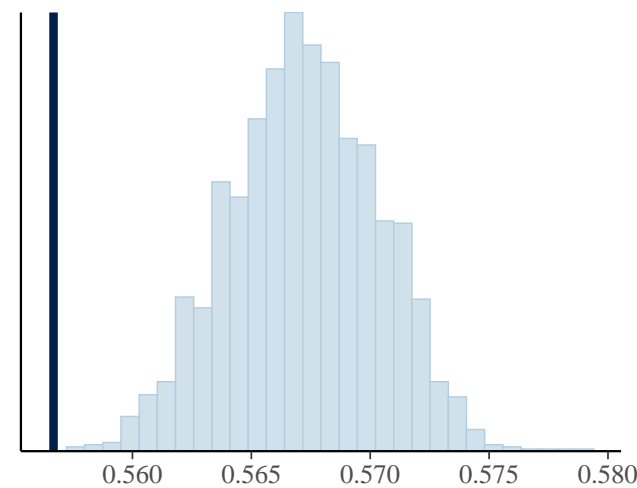
Pooled model



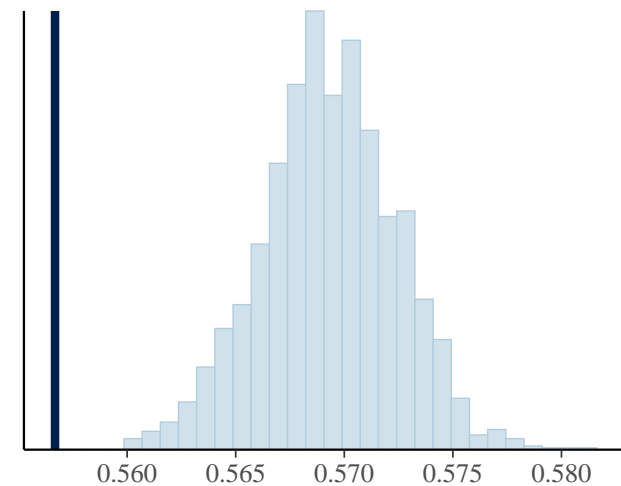
Four SCEs



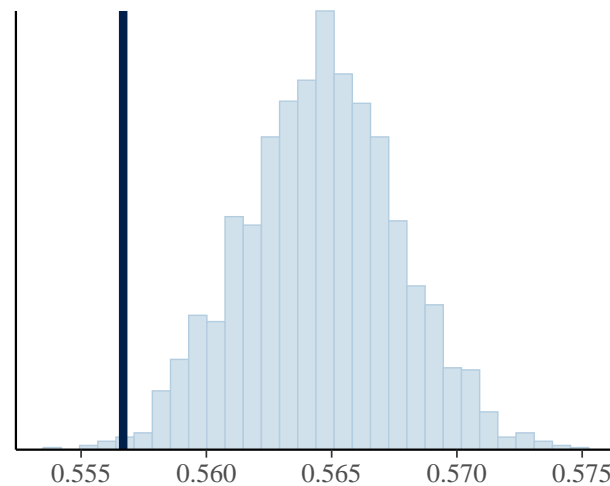
Headways



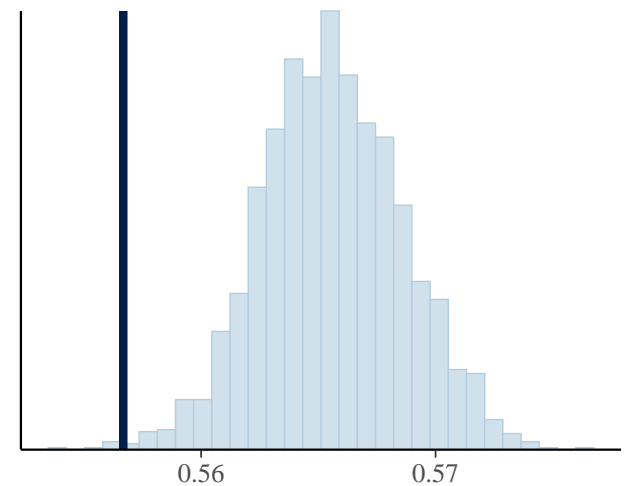
Hard brakes



Rolling stability



Collision mitigation



$T = \text{prop_zero}$ $T(y_{\text{rep}})$ $T(y)$