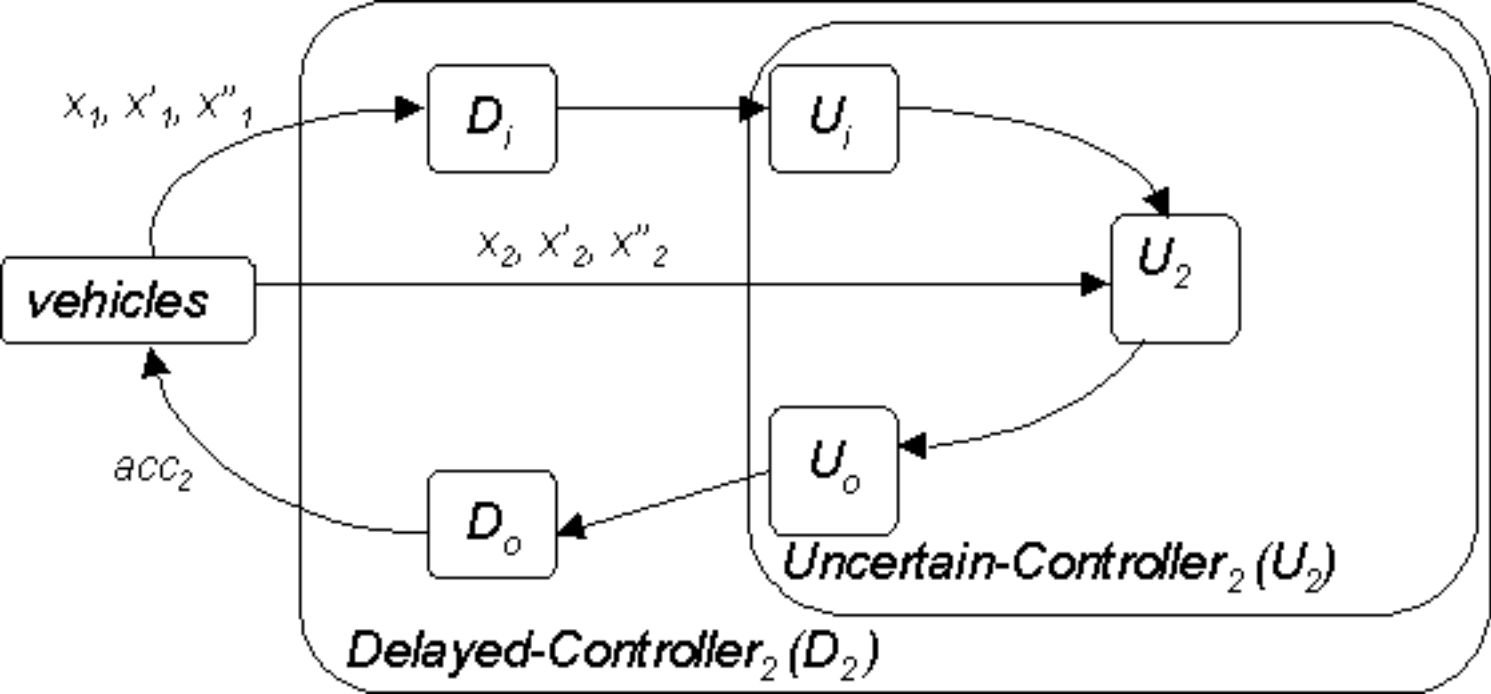
x_1, x'_1, x''_1
D_i
U_i
x_2, x'_2, x''_2
vehicles
U_2
acc_2
U_o
D_o
Uncertain-Controller$_2$ (U_2)
Delayed-Controller$_2$ (D_2)