

Motorway traffic related VACS – V2I systems

System	Description	Sources of info
Cooperative Merging (CM)	V2V or V2I cooperation is necessary to accomplish the merging function	Tampère et al, 1999; Popescu-Zeletin et al, 2010
Cooperative Variable Speed Limit System (CVSLS)	V2I cooperation is necessary so that speed limits are directly communicated to the vehicle	Grumert et al, 2013
Intelligent Speed Adaptation (ISA)	V2I cooperation is necessary to perform its functions in full extent; in an elementary form it may operate as autonomous or as V2V system	Tampère et al, 1999; Carsten and Tate, 2000, 2005; Varhelyi and Makinen, 2001; Biding and Lind, 2002; Hegeman, 2002; Hogema et al, 2002; Liu and Tate, 2004; Bishop, 2005; van Driel, 2007; Boriboonsomsin et al, 2008; Doecke and Woolley, 2010; Marchau et al, 2010; SWOV, 2010; Hoeger et al, 2011; Vlassenroot et al, 2011a, 2011b; Benmimoun et al, 2012; Blum et al, 2012; Kessler et al, 2012; iMobility Forum, 2013
Navigation System (NAVS)	V2I cooperation is necessary to receive location and route guidance information, as well as for the establishment of a “probe car” system	Eby and Kostyniuk, 1999; Pang et al, 2002; McNally et al, 2003; Flinsenberg, 2004; Jahn et al, 2005; May et al, 2005; Kaparias et al, 2007; Ma and Kaber, 2007; Lee et al, 2008; Schultes, 2008; Buscena et al, 2009; Delling and Wagner, 2009; Delling et al, 2009; Kaparias and Bell, 2009, 2010; Lavien et al, 2011; Lee and Yang, 2012; Nagaki, 2012; Skog and Händel, 2012; Belzowski and Ekstrom, 2013