



- > 📁 fig
- > 📁 images
- > 📁 plots
- 📄 main.tex
- 📄 references.bib
- 📄 reviews.docx

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Source Rich Text | Ω |
198 \newcommand{\ellambda}{\ensuremath{\rho_{\lambda}}}
199 \newcommand{\nlambda}{\ensuremath{N_{\lambda}}}
200
201 \newcommand{\pc}[1]{\color{red} \textbf{PC:} #1}
202 \newcommand{\ms}[1]{\color{blue}#1}
203
204 \newcommand{\rissim}{CooperIS}
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206
207 \begin{document}
208
209
210 \title{On the Feasibility of RIS-enabled Cooperative Driving}
211
212
213 \author{
214 \IEEEauthorblockN{Michele Segata\IEEEauthorrefmark{1}, Paolo Casari\IE
Tyrovolas\IEEEauthorrefmark{3}, \Tagwa Saeed\IEEEauthorrefmark{4}, G
Liaskos\IEEEauthorrefmark{6}}\
215 \IEEEauthorblockA{\IEEEauthorrefmark{1}Department of Information Engin
216 \IEEEauthorblockA{\IEEEauthorrefmark{2}Dept. of Electrical Engineering
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220 \IEEEauthorblockA{\IEEEauthorrefmark{5}Cyber Security Systems and Appl
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222 \IEEEauthorblockA{\IEEEauthorrefmark{6}Dept. of Computer Science and Engin
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225 }
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227 \maketitle
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229 \begin{abstract}
230 \nohyphens{%
231 Future cooperative autonomous vehicles will require high-performance commu
perception. The high-bandwidth requirements of these functions can be met
propagation conditions of typical vehicular environments. A solution to th
configurable direction, and have recently gained attention in the vehicula
challenges ahead and the performance \acp{RIS} need to deliver in order to
framework for \acp{RIS} integrated into the P\lexe/Veins/SUMO ecosystem \ms
232 }
233 \end{abstract}
234
235 %%\begin{IEEEkeywords}
236 %%\platooning
237 %%\end{IEEEkeywords}
238
239 \acresetall
240 \acusedfMAC

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File outline

- Introduction and Related...
- Communication Models
 - \ac{RIS} model
 - Channel model
 - Model implementation
- Simulation scenarios
- Results and analysis
 - Impact of the numbe...
 - Perfect tracking scen...
 - No tracking scenario
- Conclusions
- Acknowledgment