Prediction of ego vehicle about the motion of surrounding vehicle based on its states (go straight / turn left)

 $t = t_2$ (left turn)

Ego Vehicle



 $t = t_0$

 $t = t_1 \text{ (left turn)}$

Driver Behavior Model



 $t = t_1 \text{ (straight)}$

 $t = t_2 \text{ (straight)}$

 $t = t_1$ (yield)

 $t = t_0$