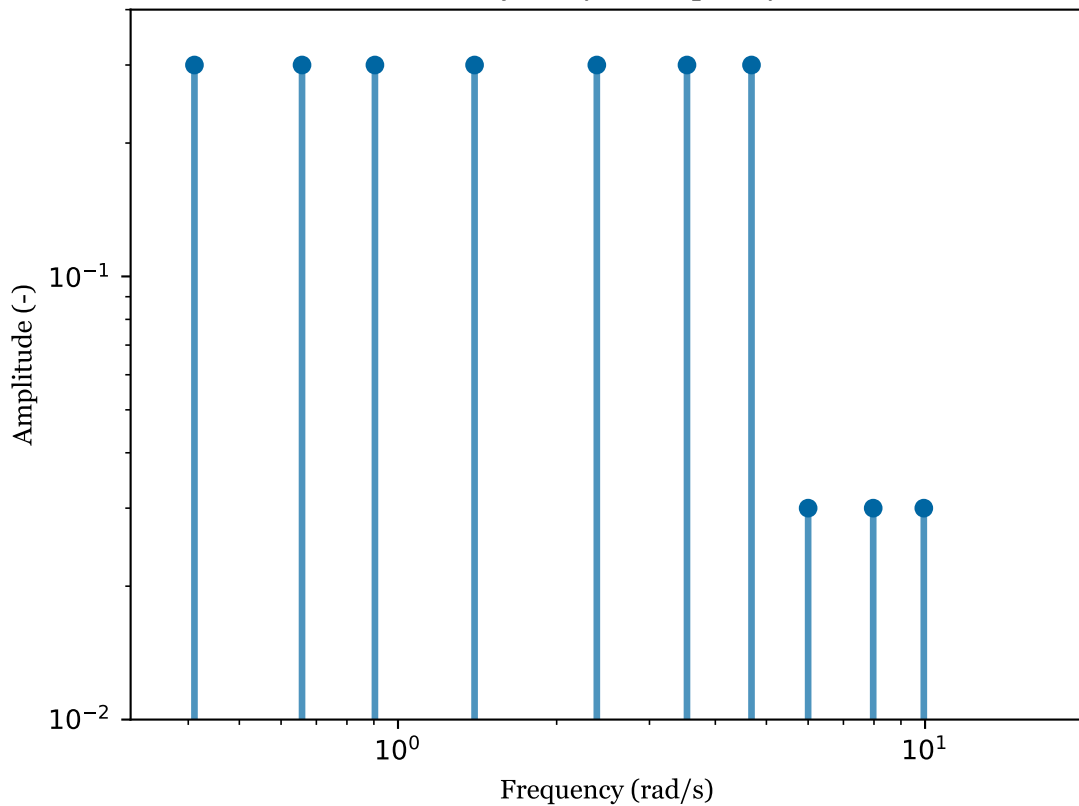
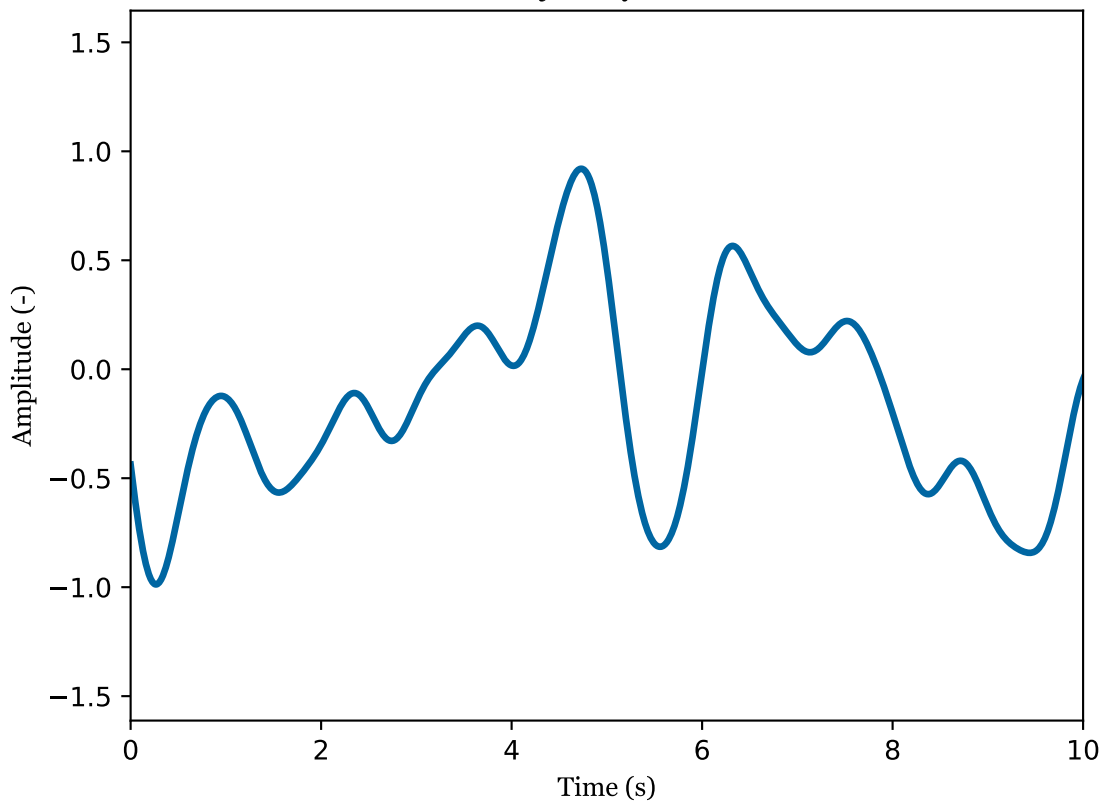
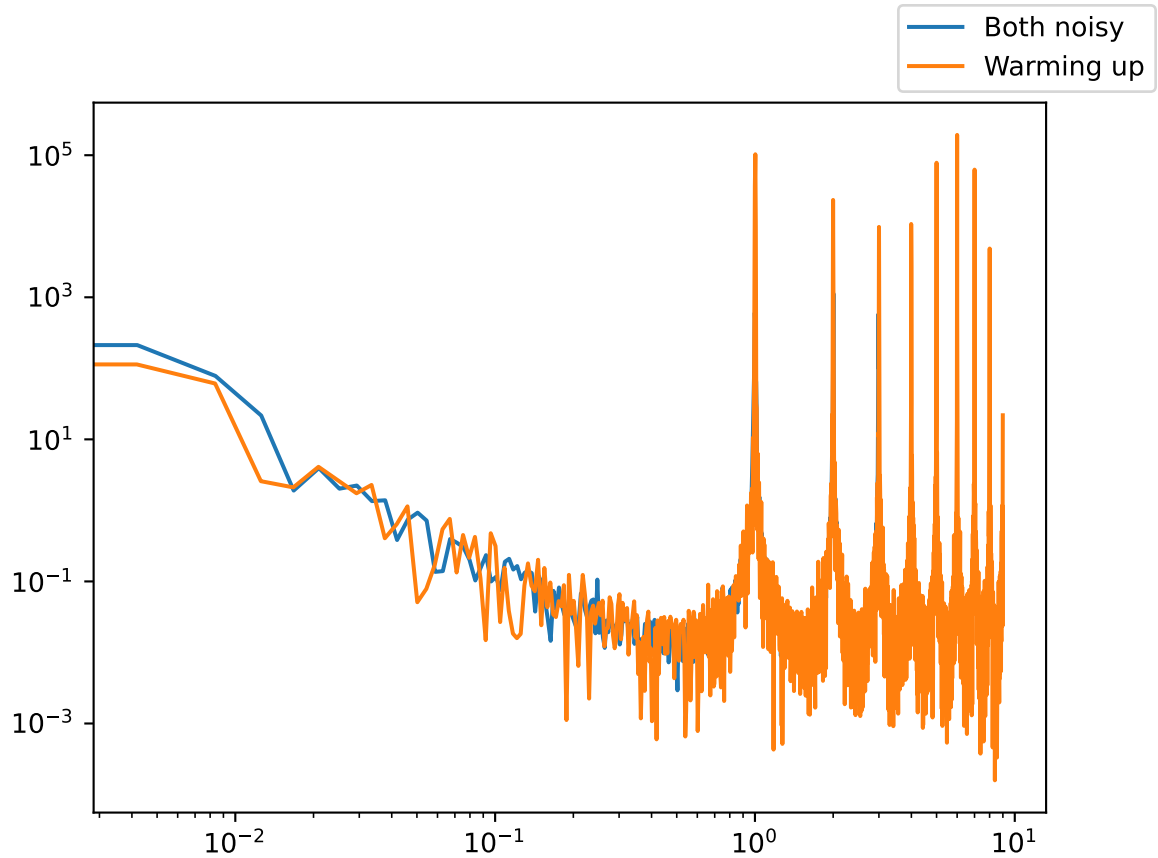


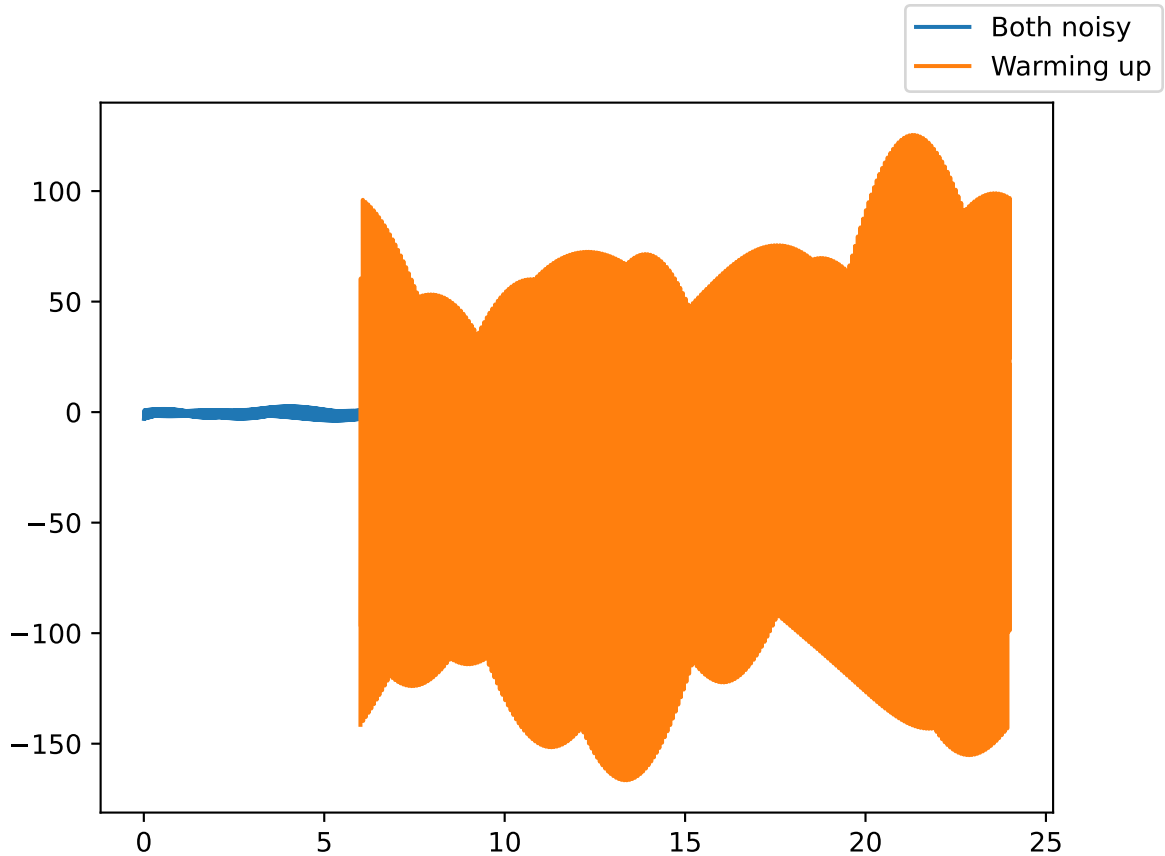
Reference trajectory in frequency domain

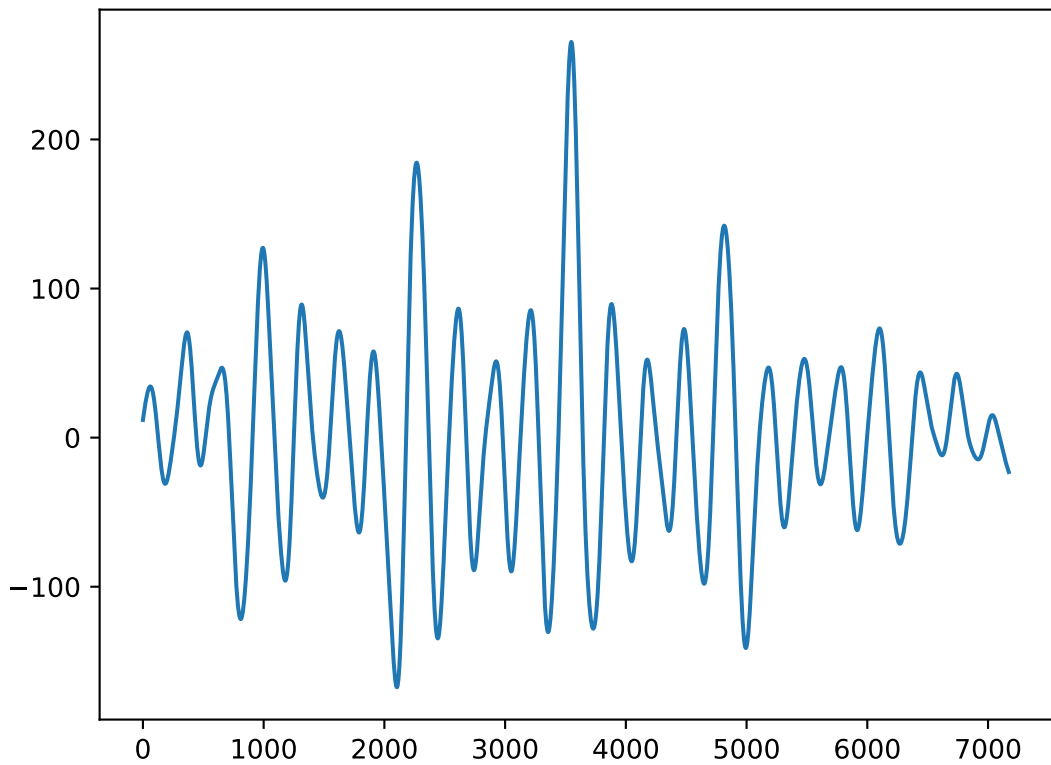


Reference trajectory in time domain

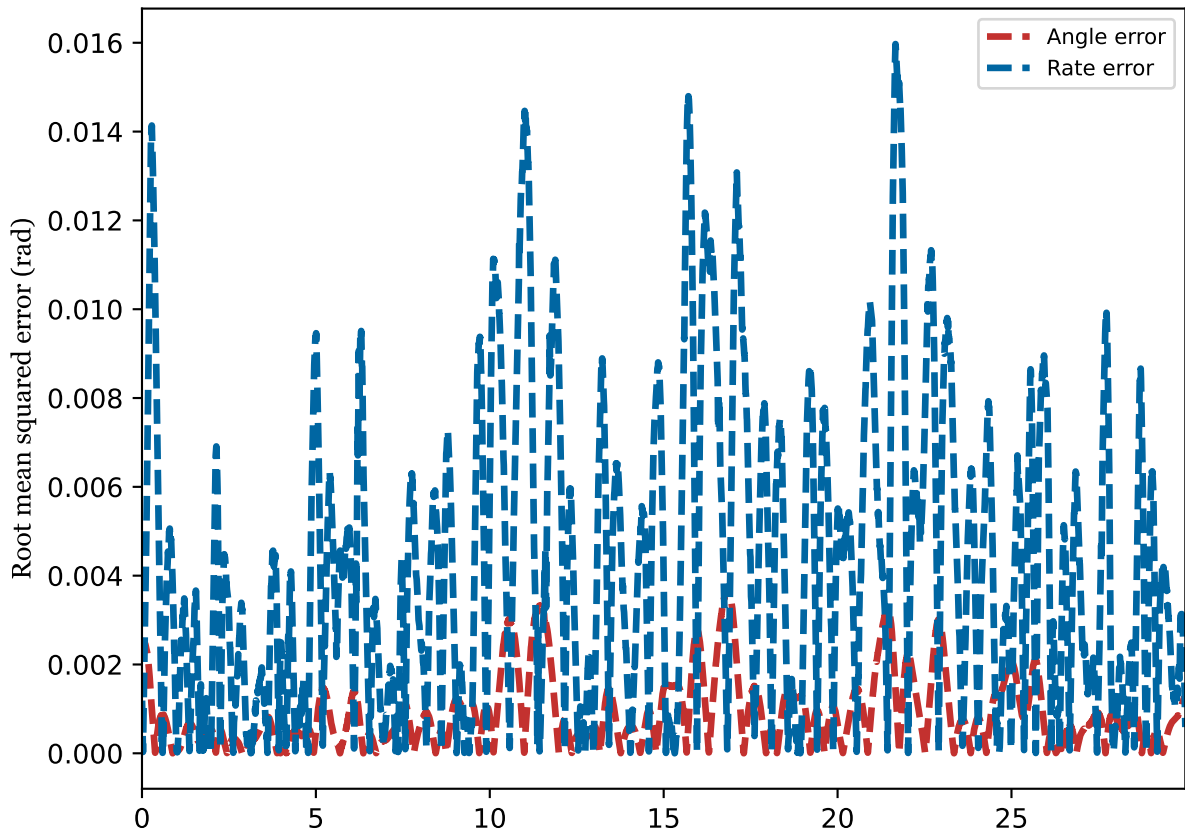




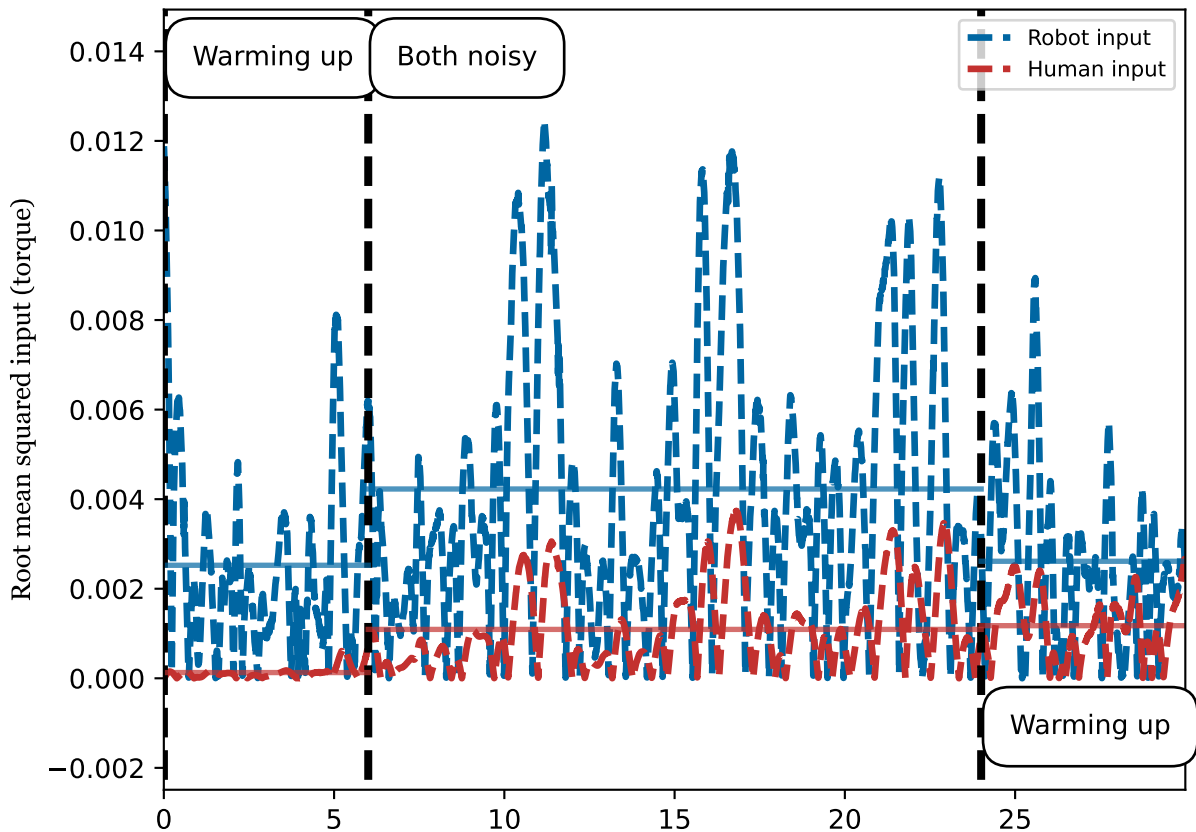




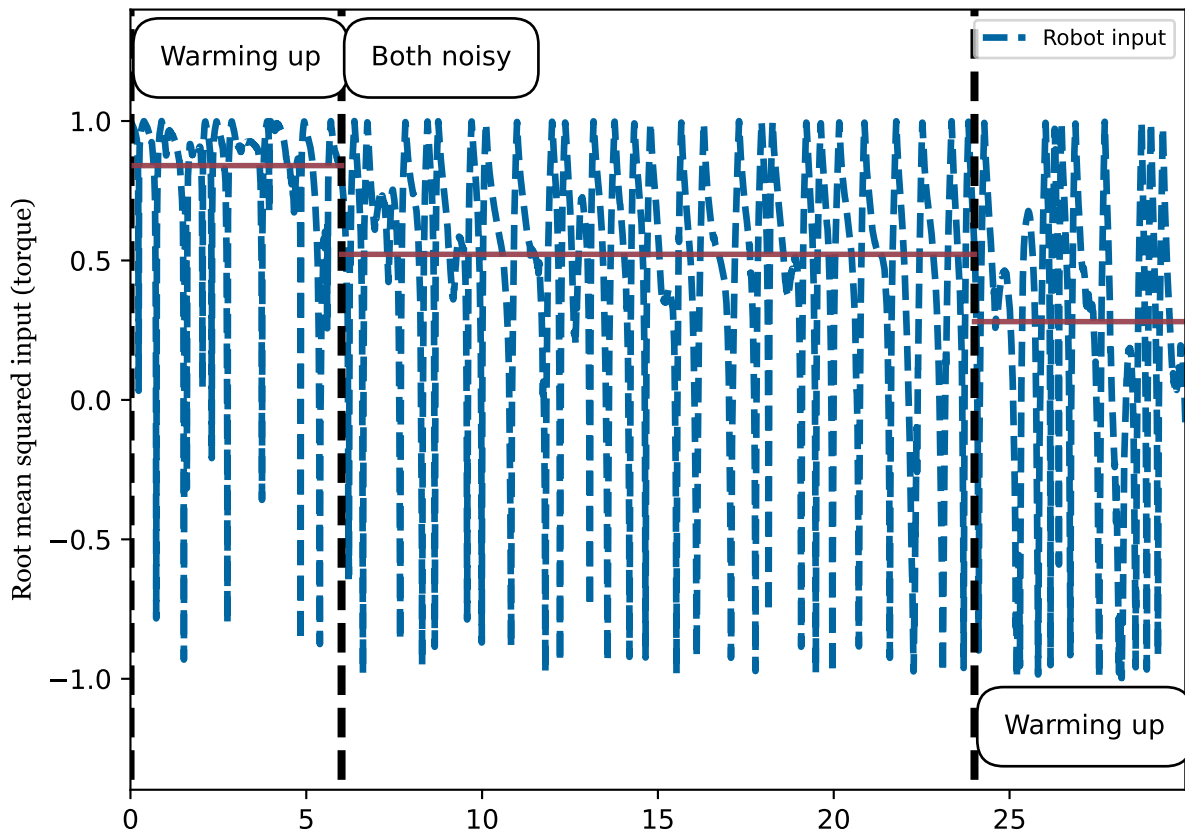
Performance (RMSE)



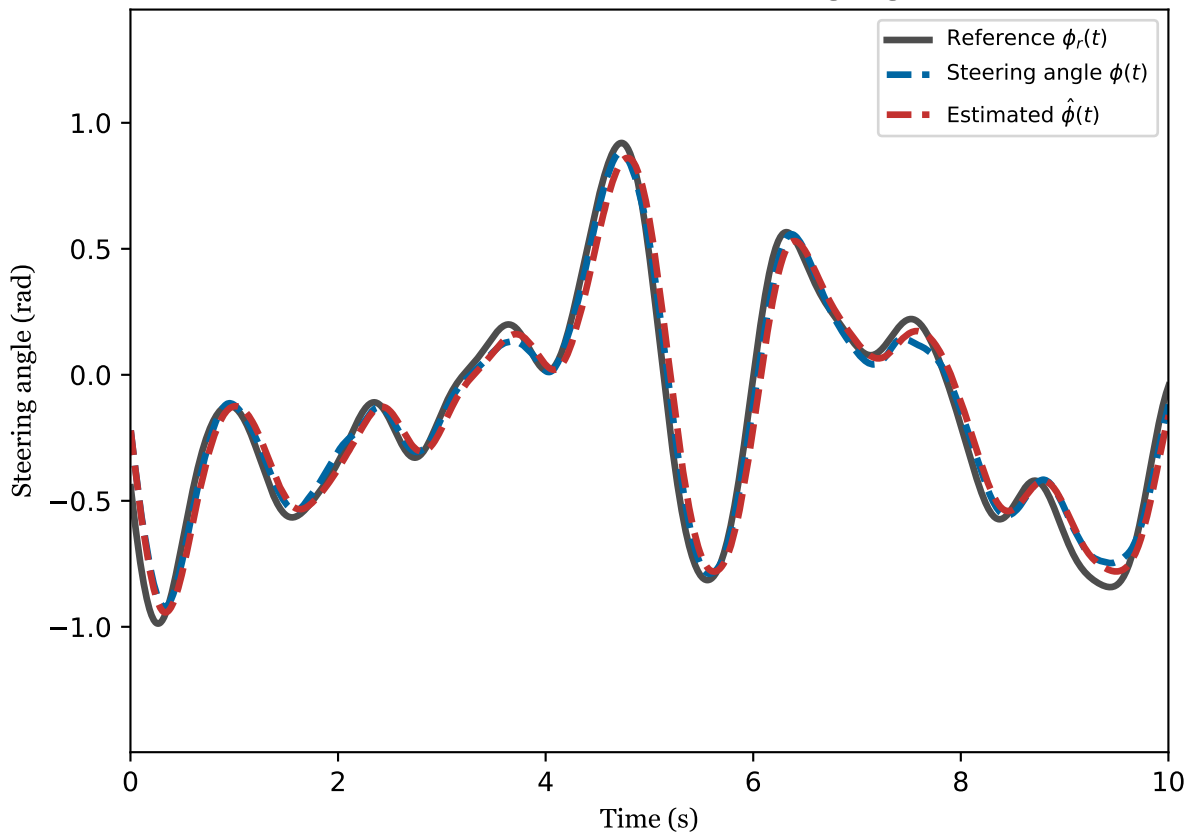
Effort (RMSU)



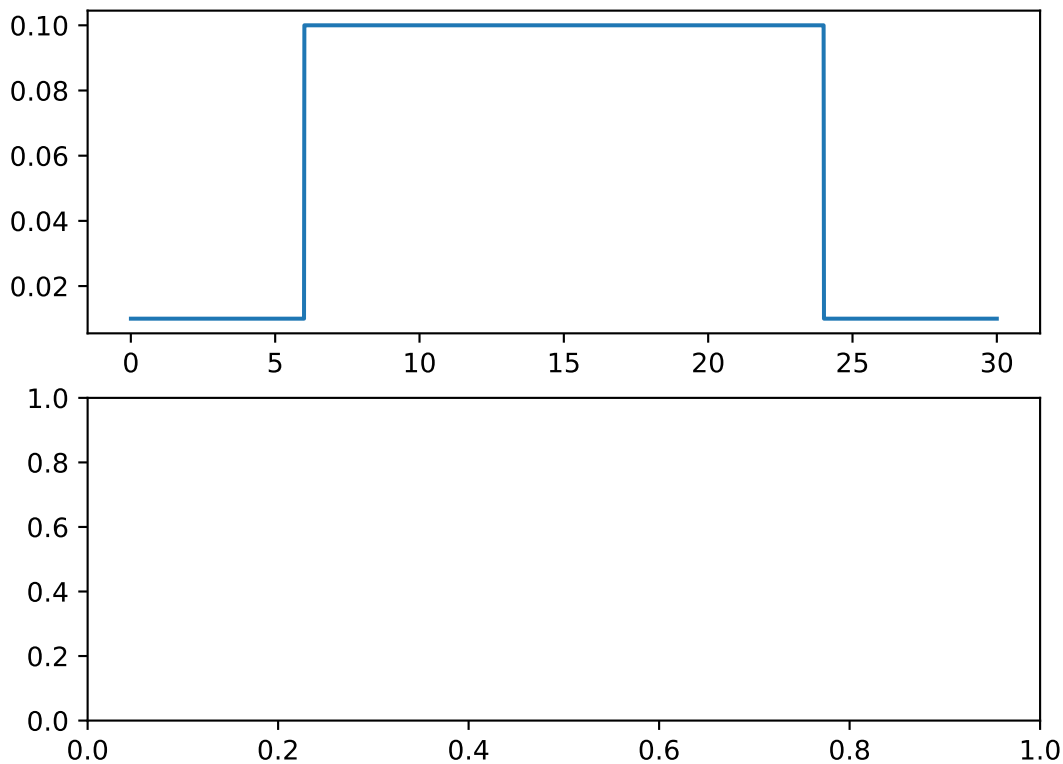
Dominance



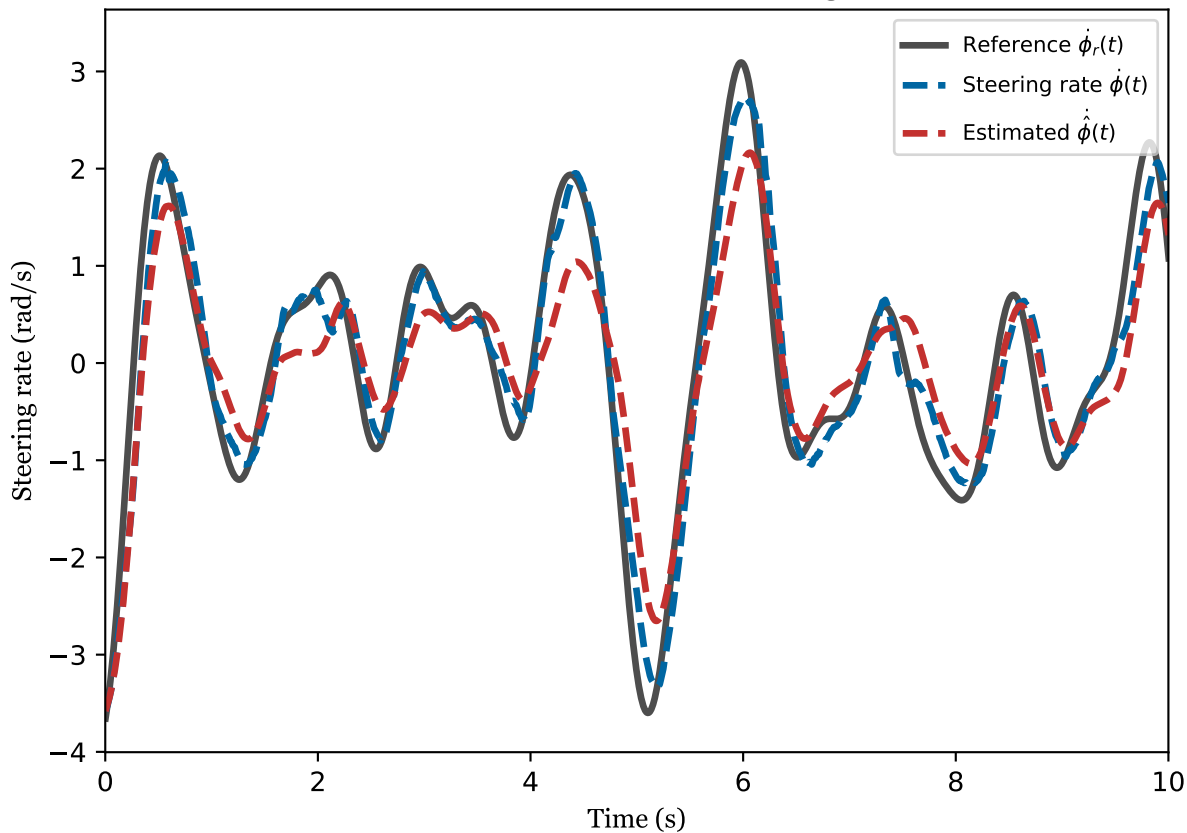
Measured and estimated steering angle



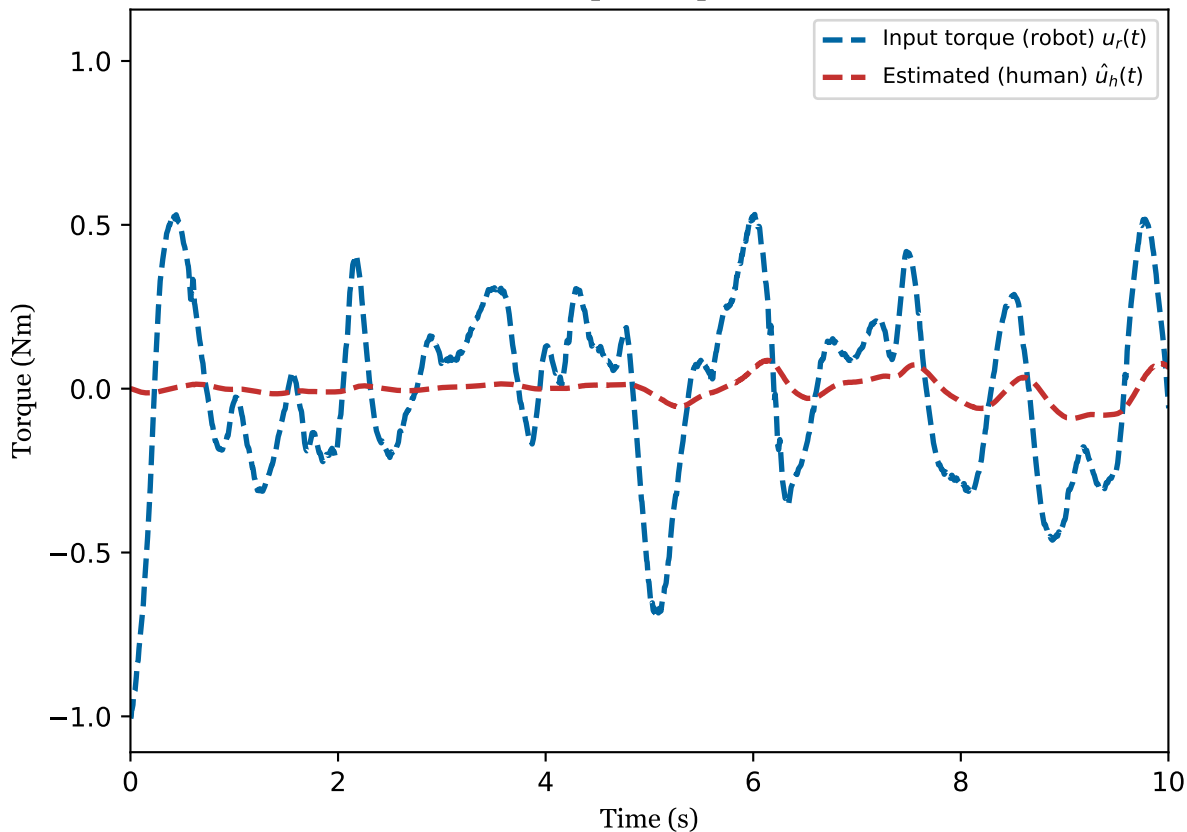
Noise variance



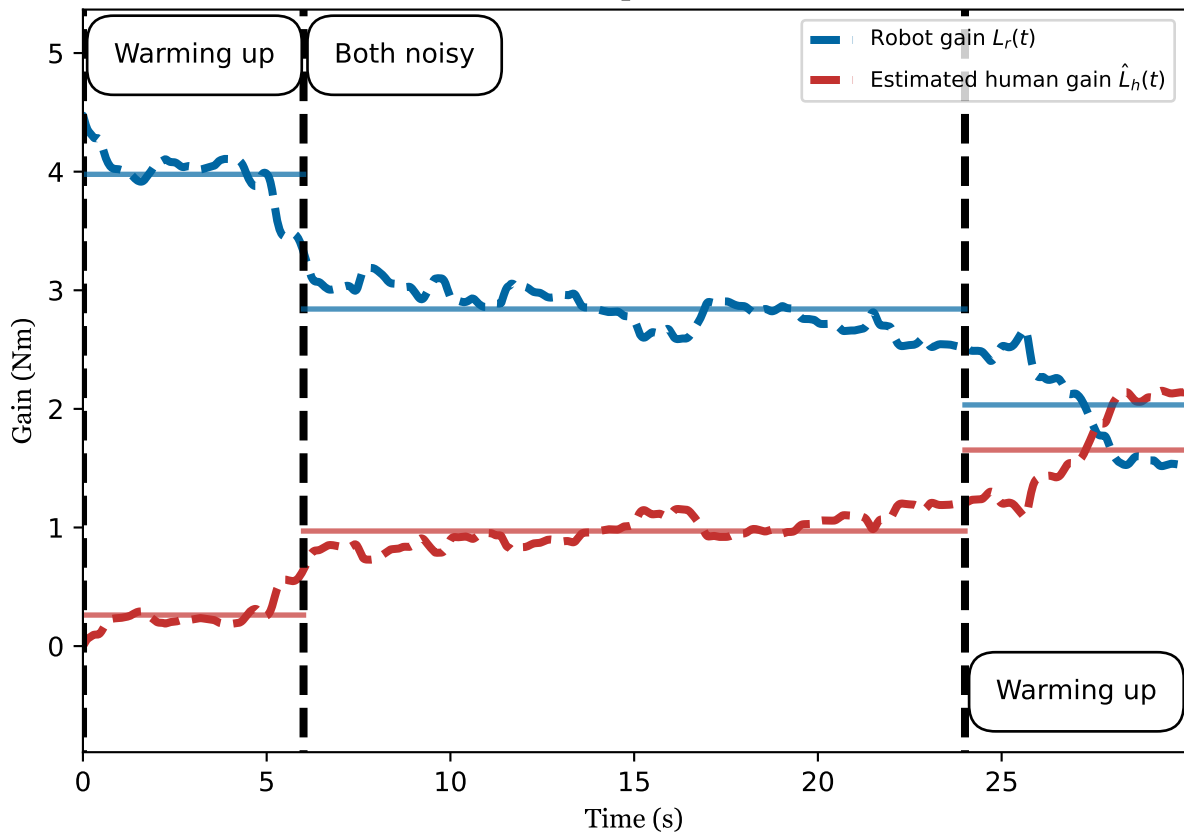
Measured and estimated steering rate



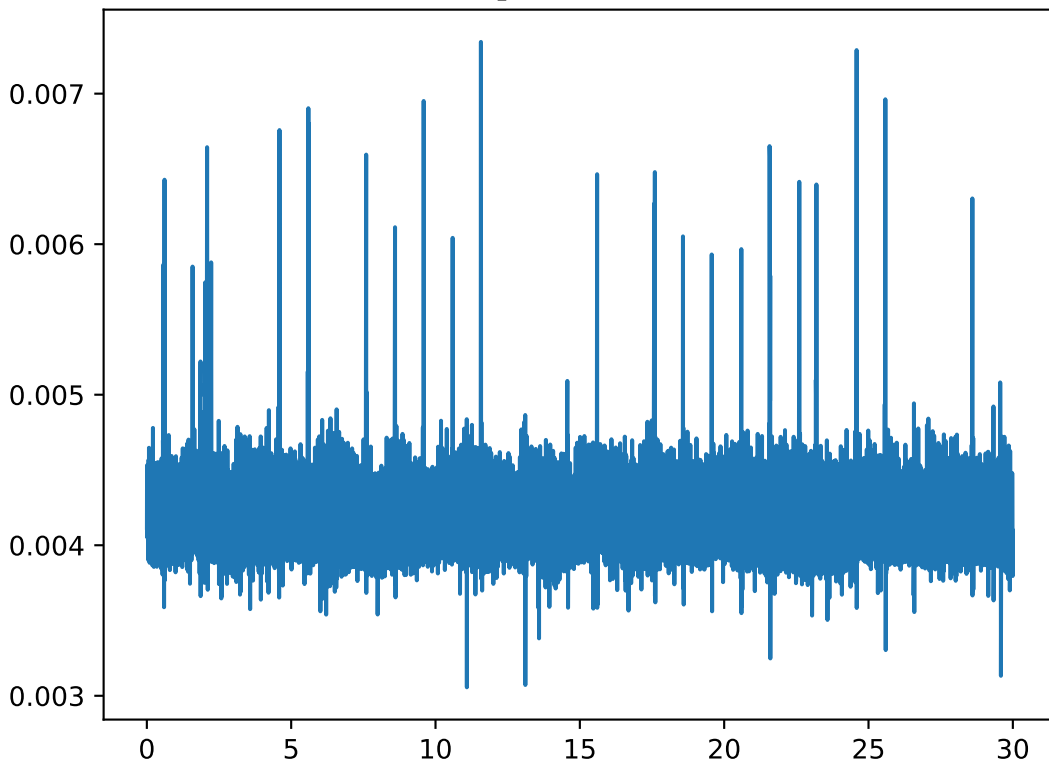
Input torque



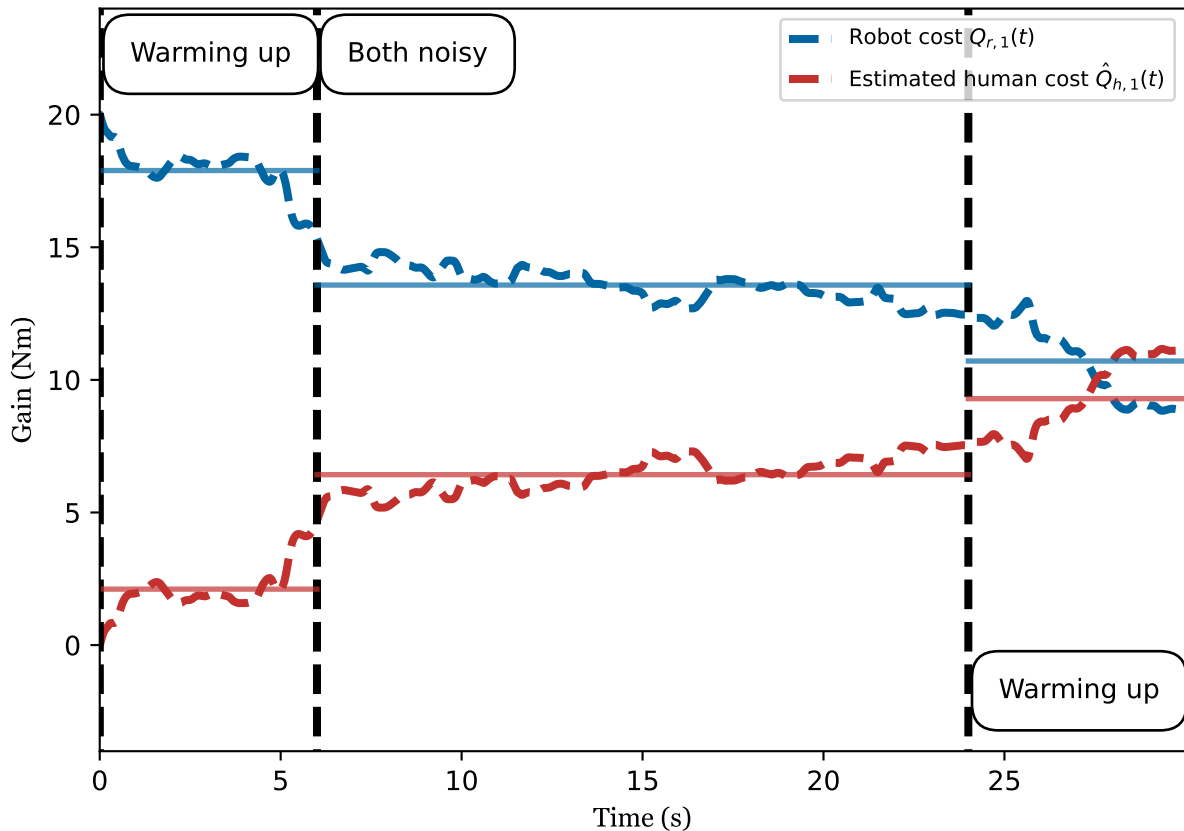
Gains position



Computational times



Cost function weights



Cost function weights

