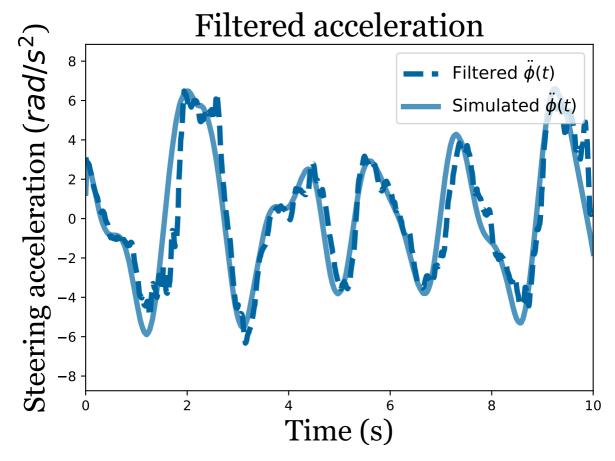
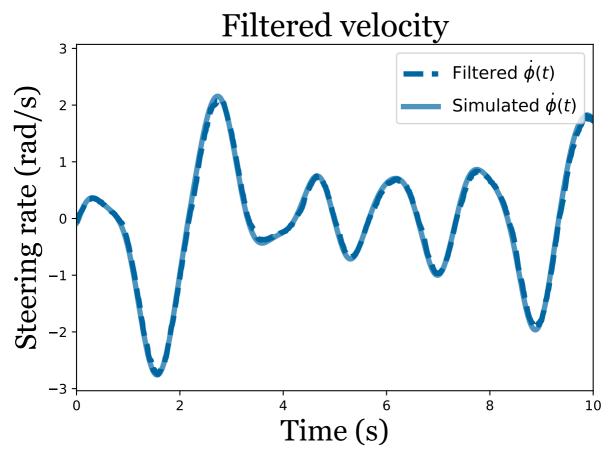


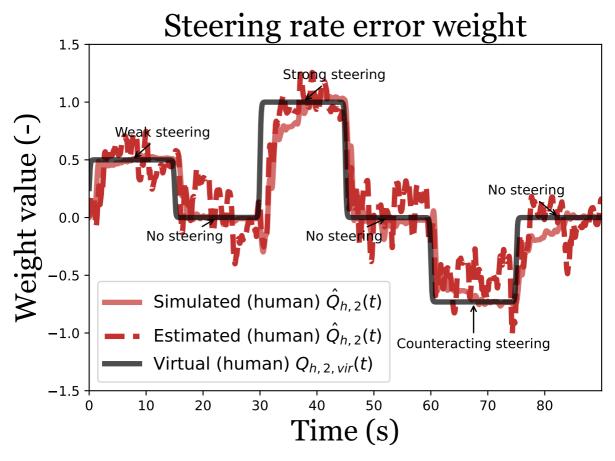
Measured and estimated steering angle Reference  $\phi_r(t)$ 1.0 Steering angle  $\phi(t)$ Steering angle (rad)Simulated  $\phi_{sim}(t)$ Estimated  $\hat{\phi}(t)$ -1.510 Time (s)

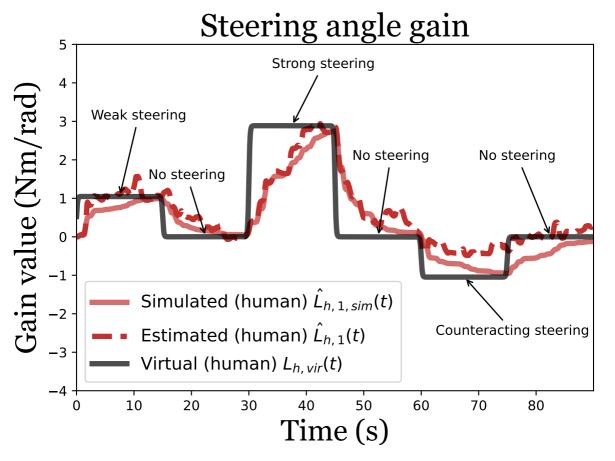


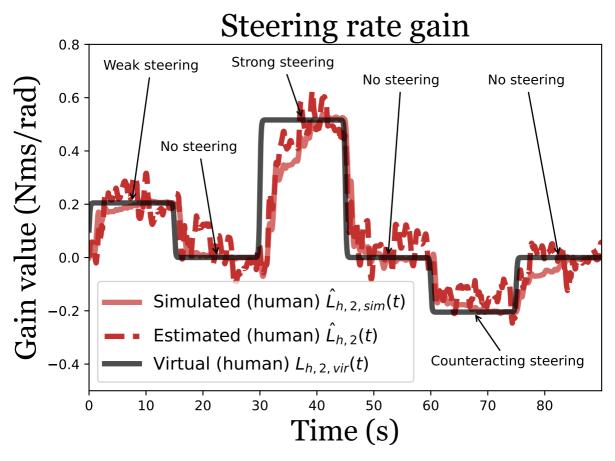


Measured and estimated steering rate 3 Steering angle (rad) Reference  $\phi_r(t)$ Steering rate  $\phi(t)$ Simulated  $\phi_{sim}(t)$ Estimated  $\hat{\phi}(t)$ 10 Time (s)

Steering angle error weight Strong steering 30 20 Weight value (-) Weak steering No steering 10 0 No steering No steering -10Simulated (human)  $\hat{Q}_{h,1}(t)$ Estimated (human)  $\hat{Q}_{h,1}(t)$ -20 Virtual (human)  $Q_{h, 1, vir}(t)$ Counteracting steering -3010 20 30 40 50 60 70 80 Time (s)







Steering angle error weight Strong steering 40 Weak steering 30 Weight value (-) 20 No steering No steering 10 0 No steering -10Estimated (human)  $\hat{Q}_{h,1}(t)$ Virtual (human)  $Q_{h, 1, vir}(t)$ -20Counteracting steering 10 20 30 40 50 60 80 70 Time (s)

