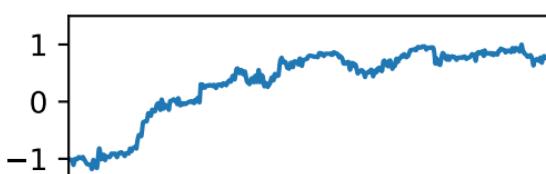
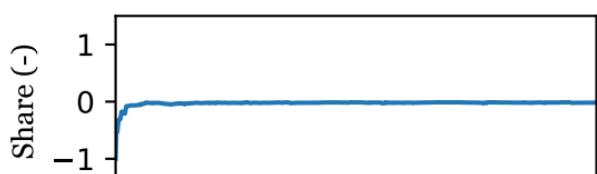
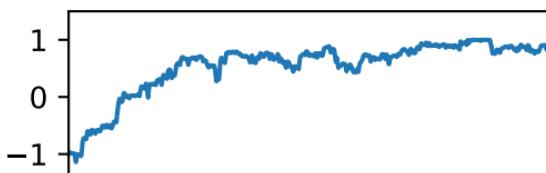
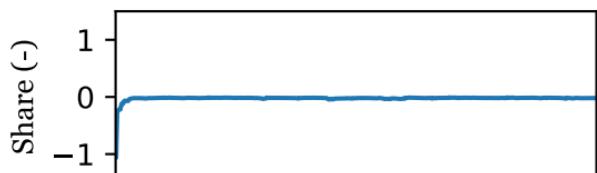
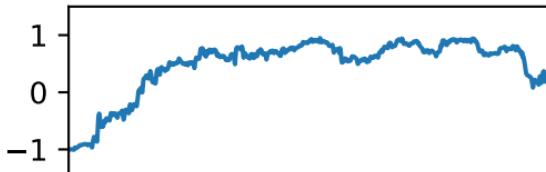
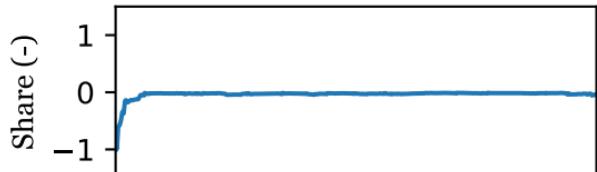
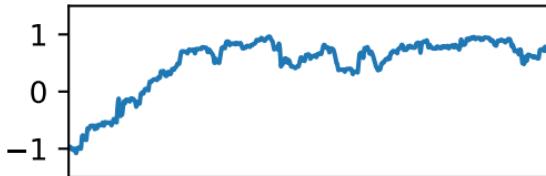


Estimated control share

Positive re.



Negative re.

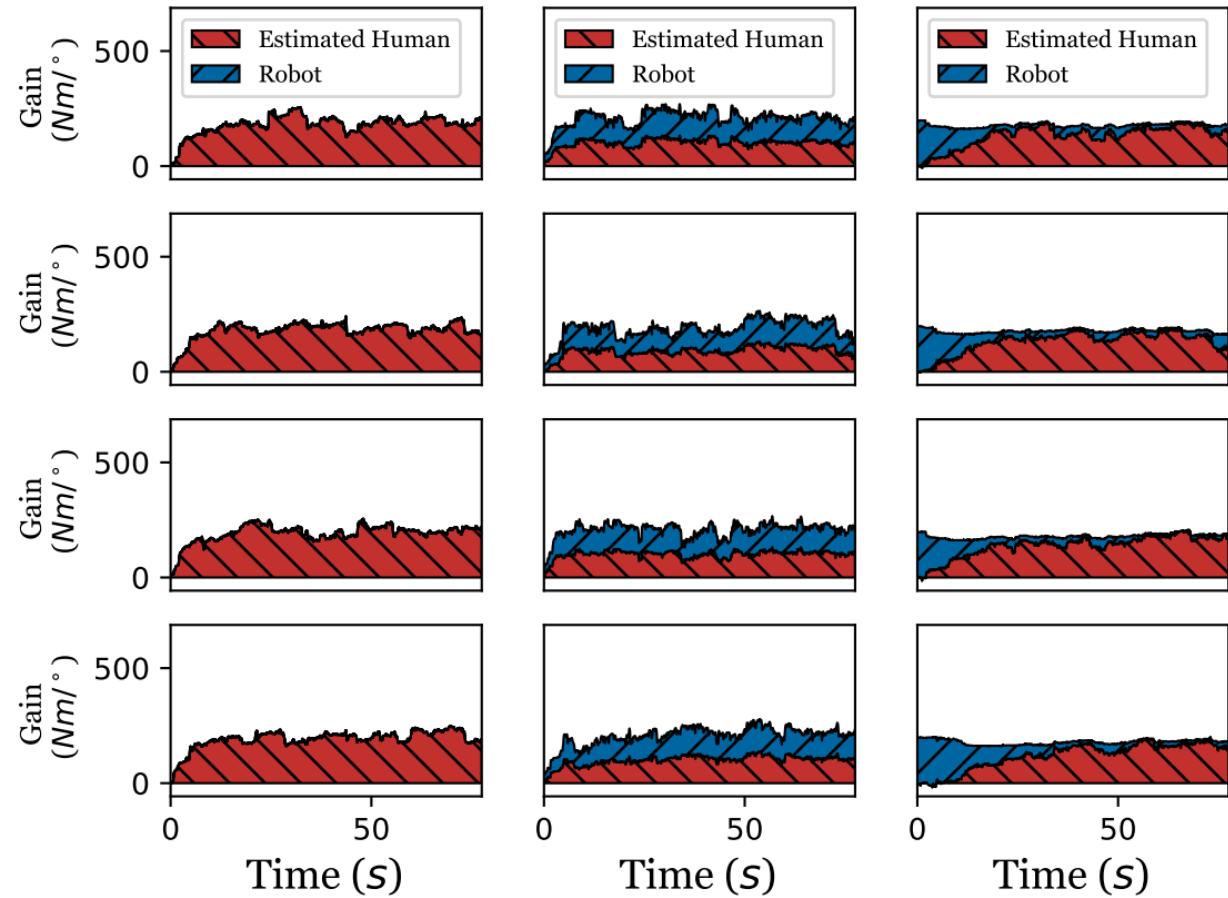


Controller gain distribution

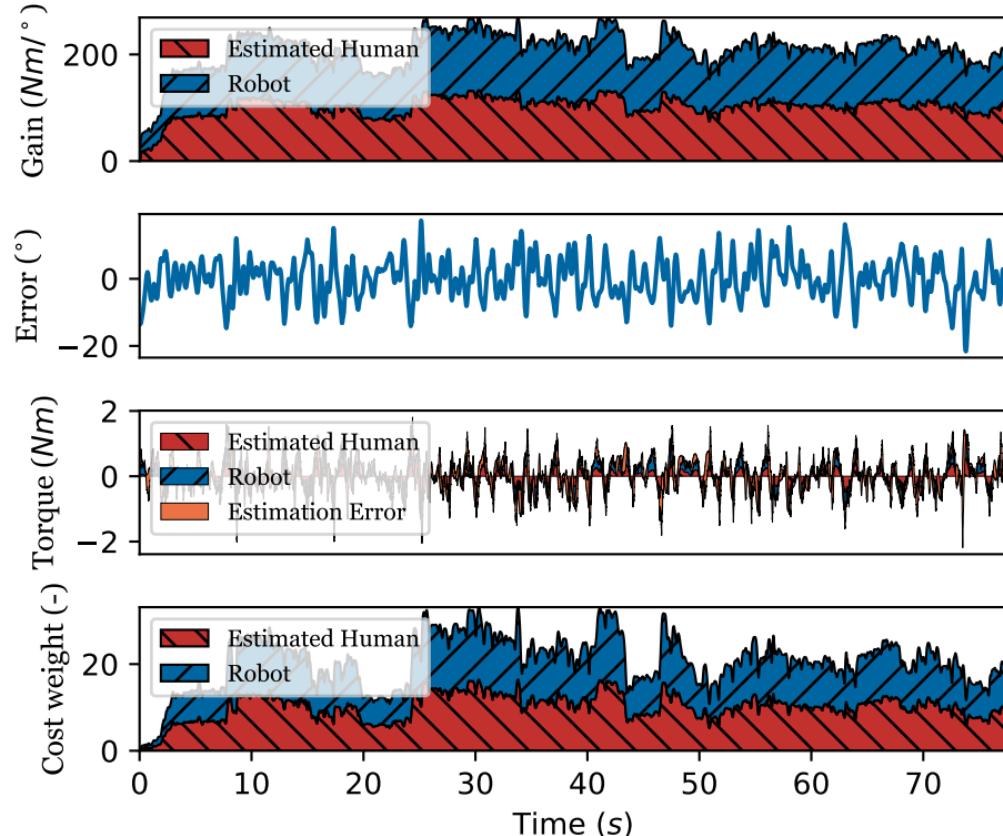
Manual

Positive re.

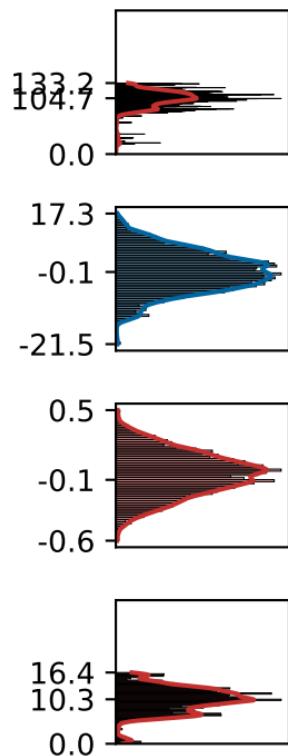
Negative re.



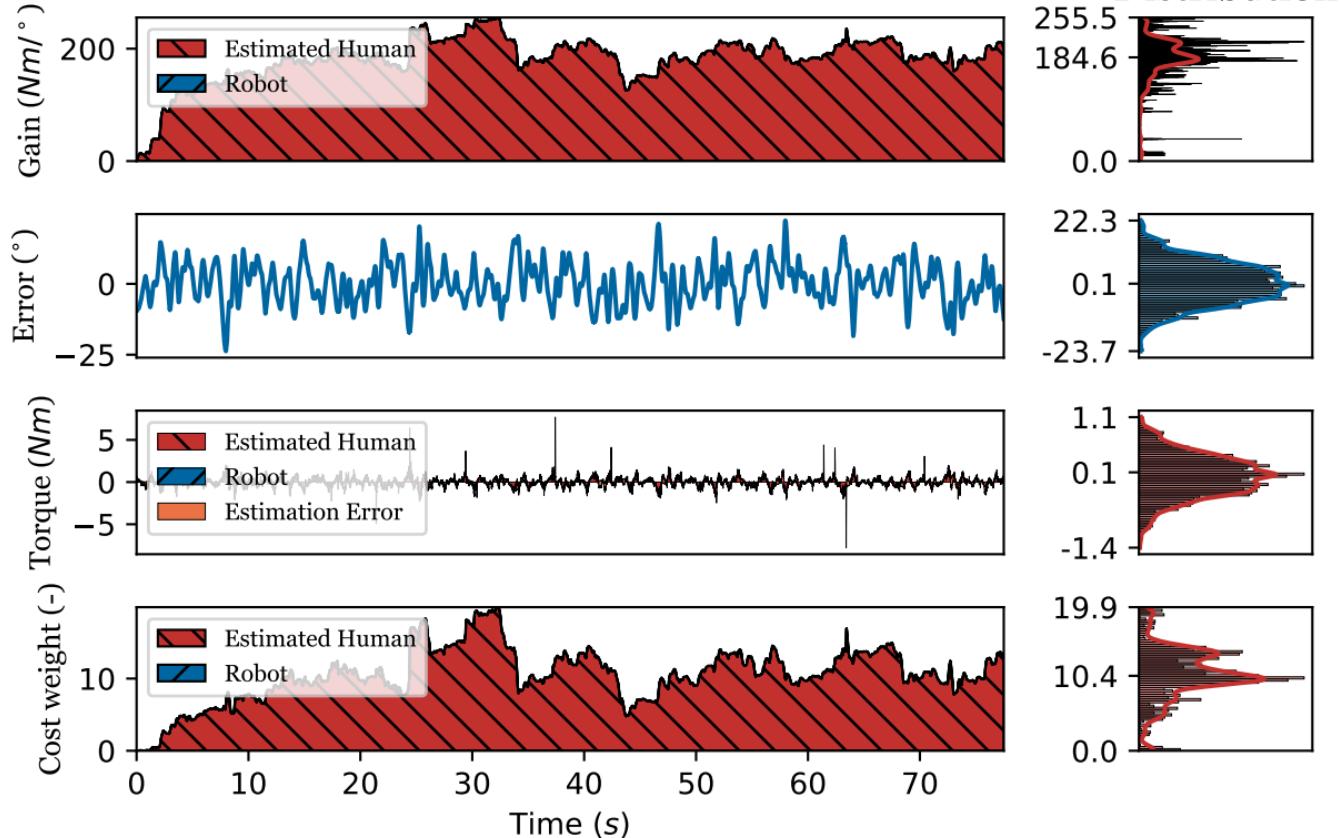
Positive Reinforcement



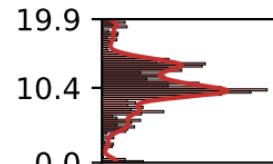
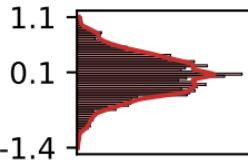
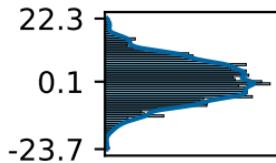
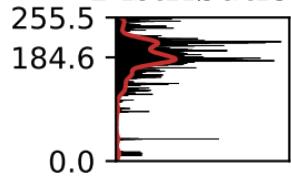
Distribution



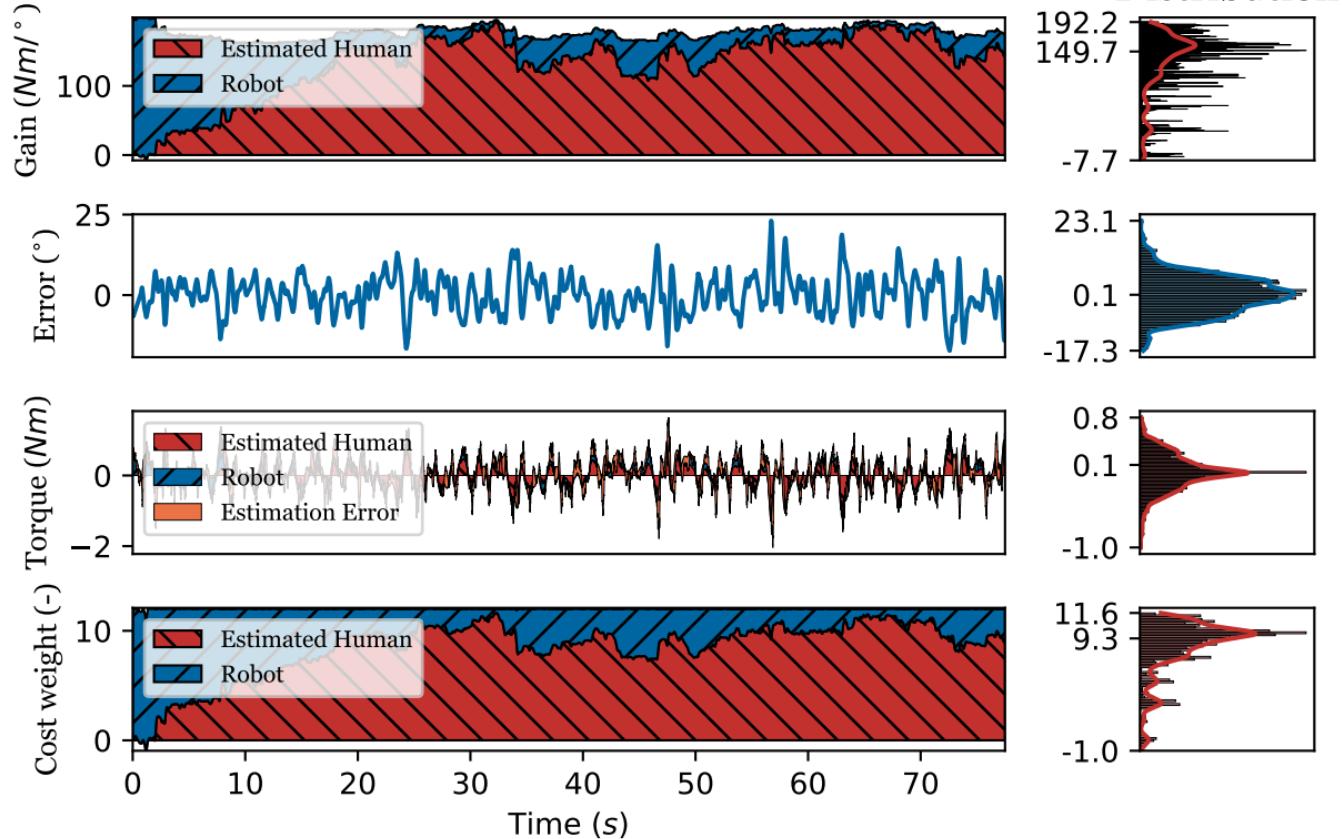
Manual Control



Distribution



Negative Reinforcement

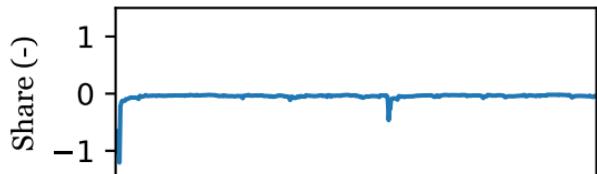
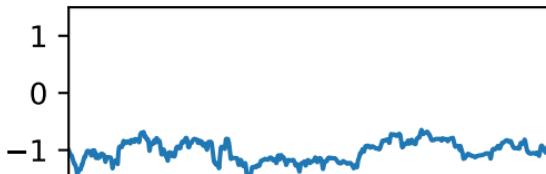
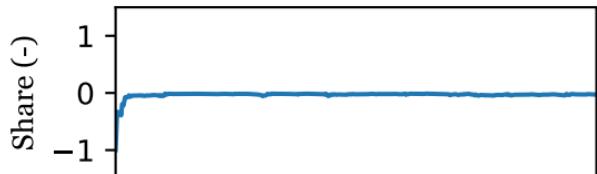
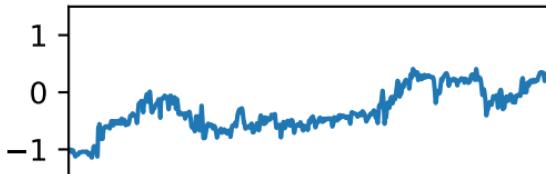
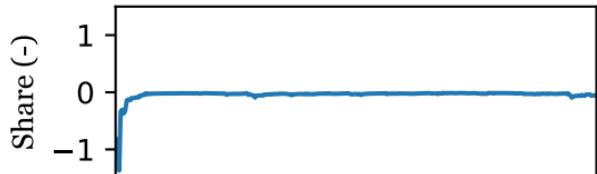
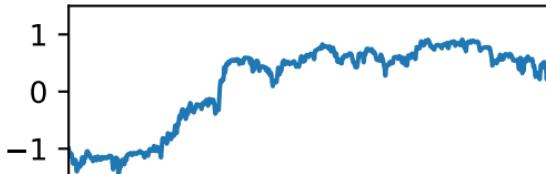


Estimated control share

Positive re.



Negative re.



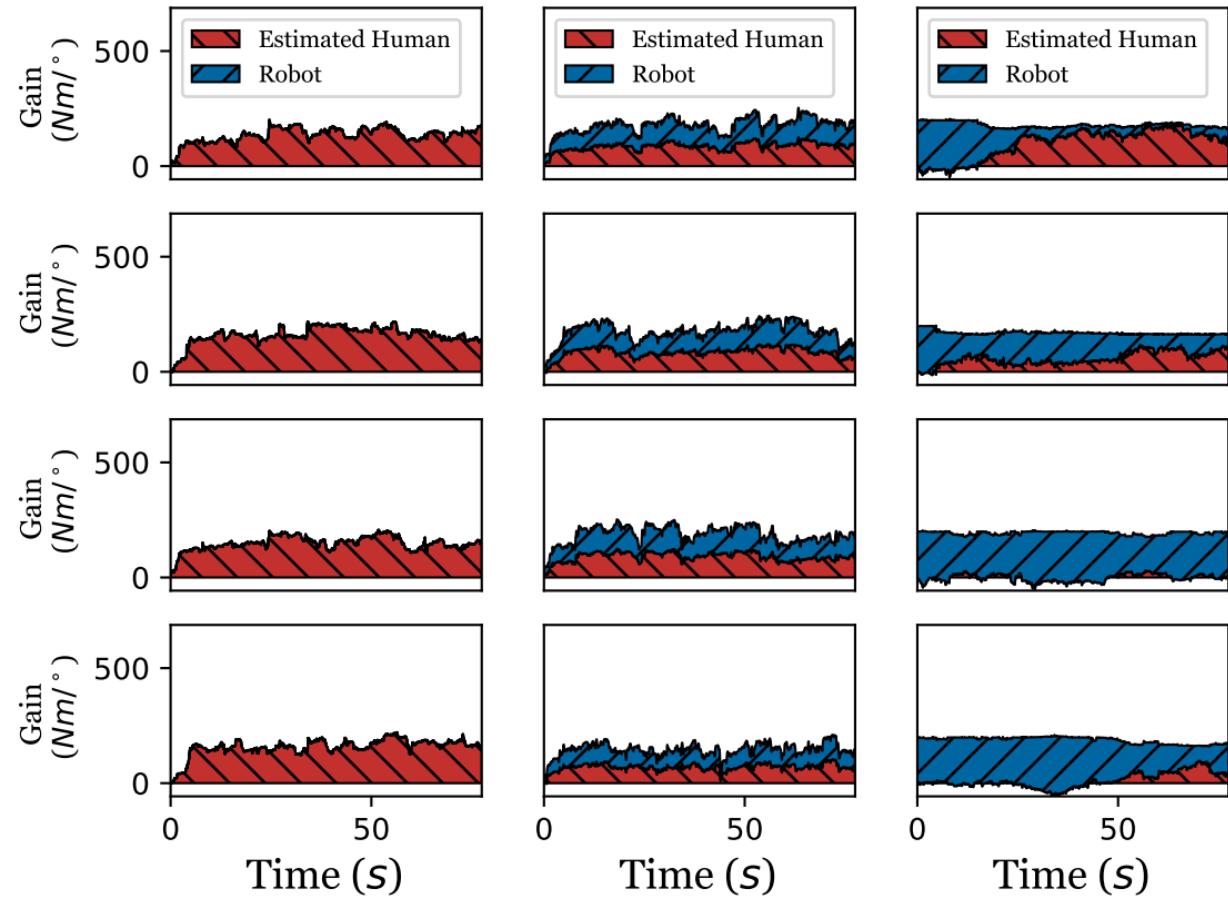
Time (s)

Controller gain distribution

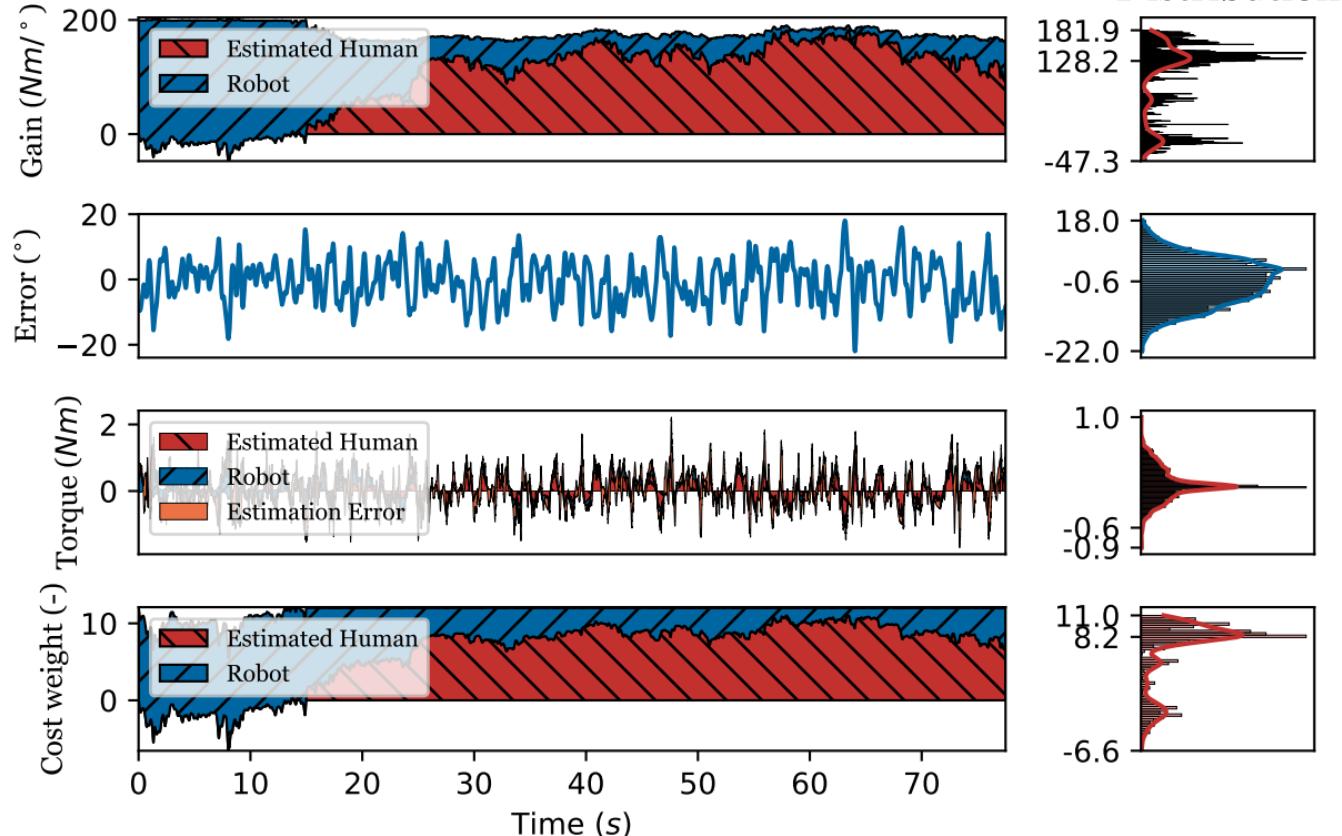
Manual

Positive re.

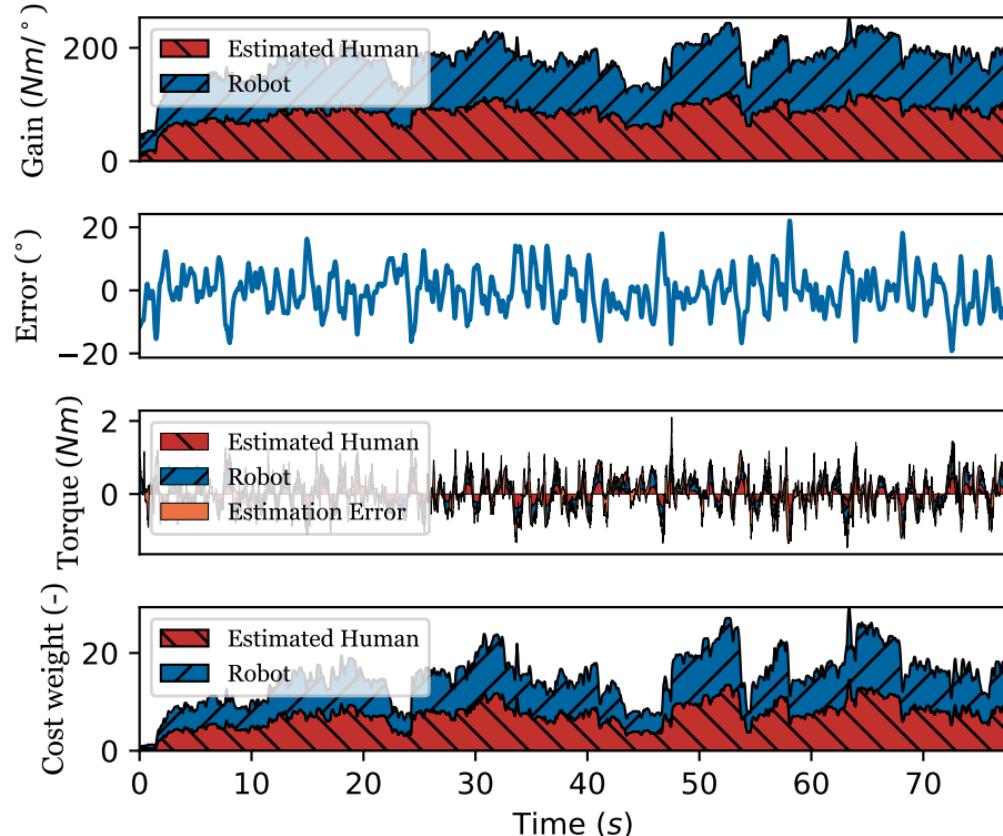
Negative re.



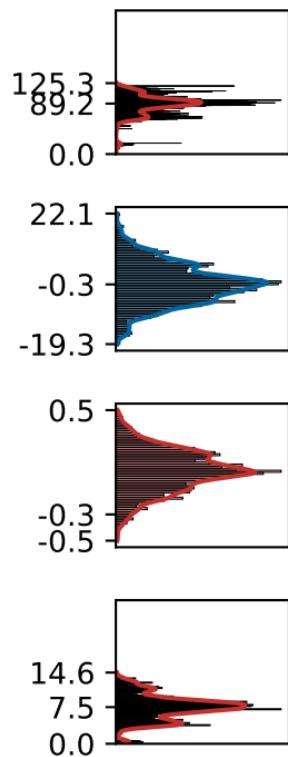
Negative Reinforcement



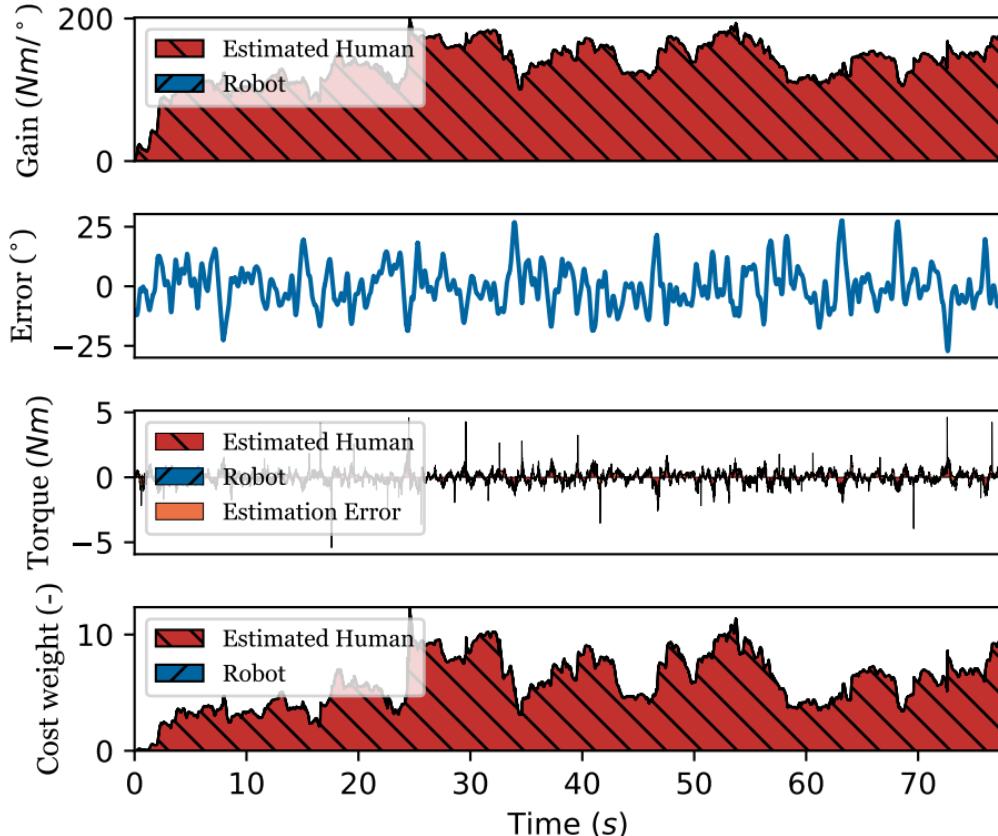
Positive Reinforcement



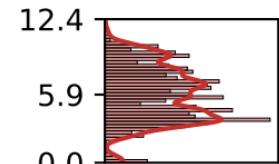
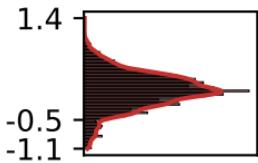
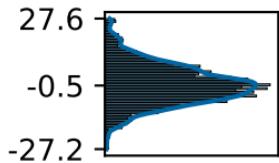
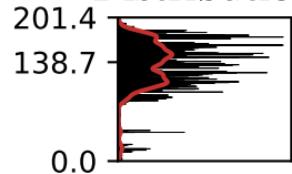
Distribution



Manual Control

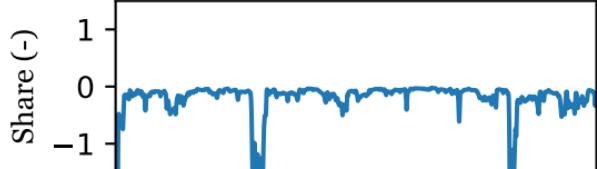


Distribution

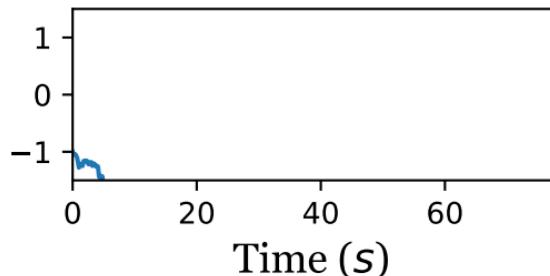
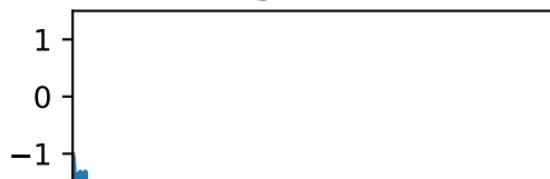
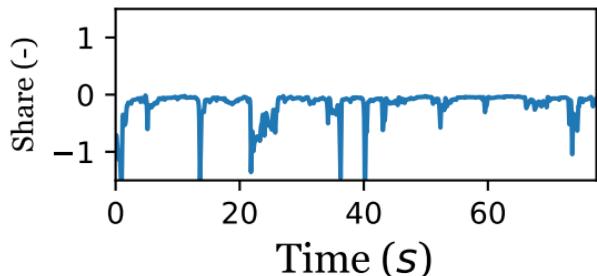
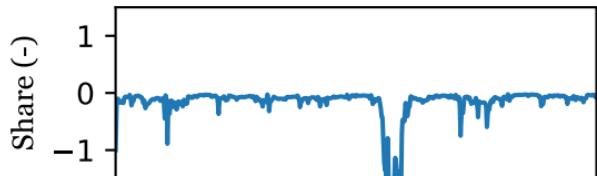
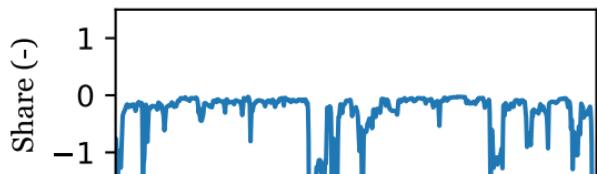


Estimated control share

Positive re.



Negative re.

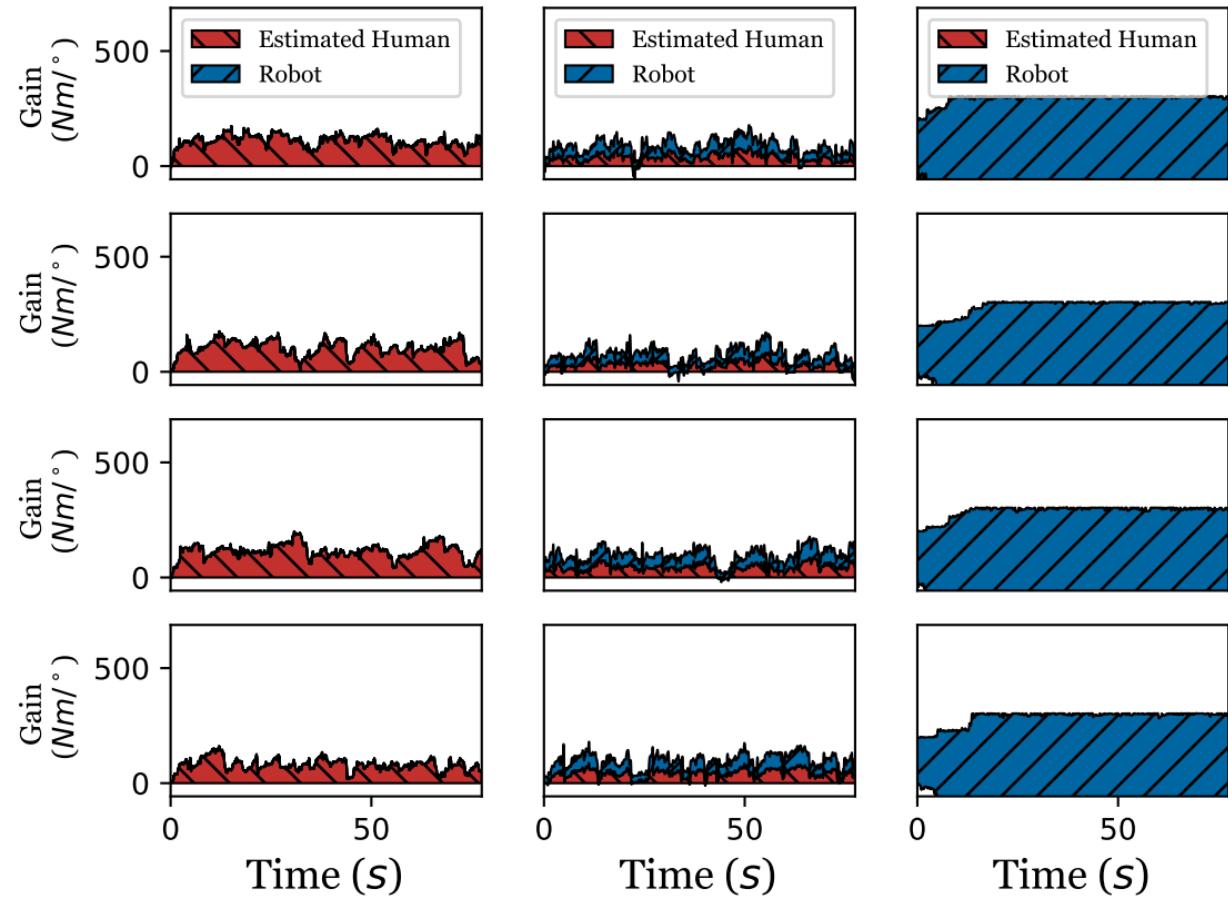


Controller gain distribution

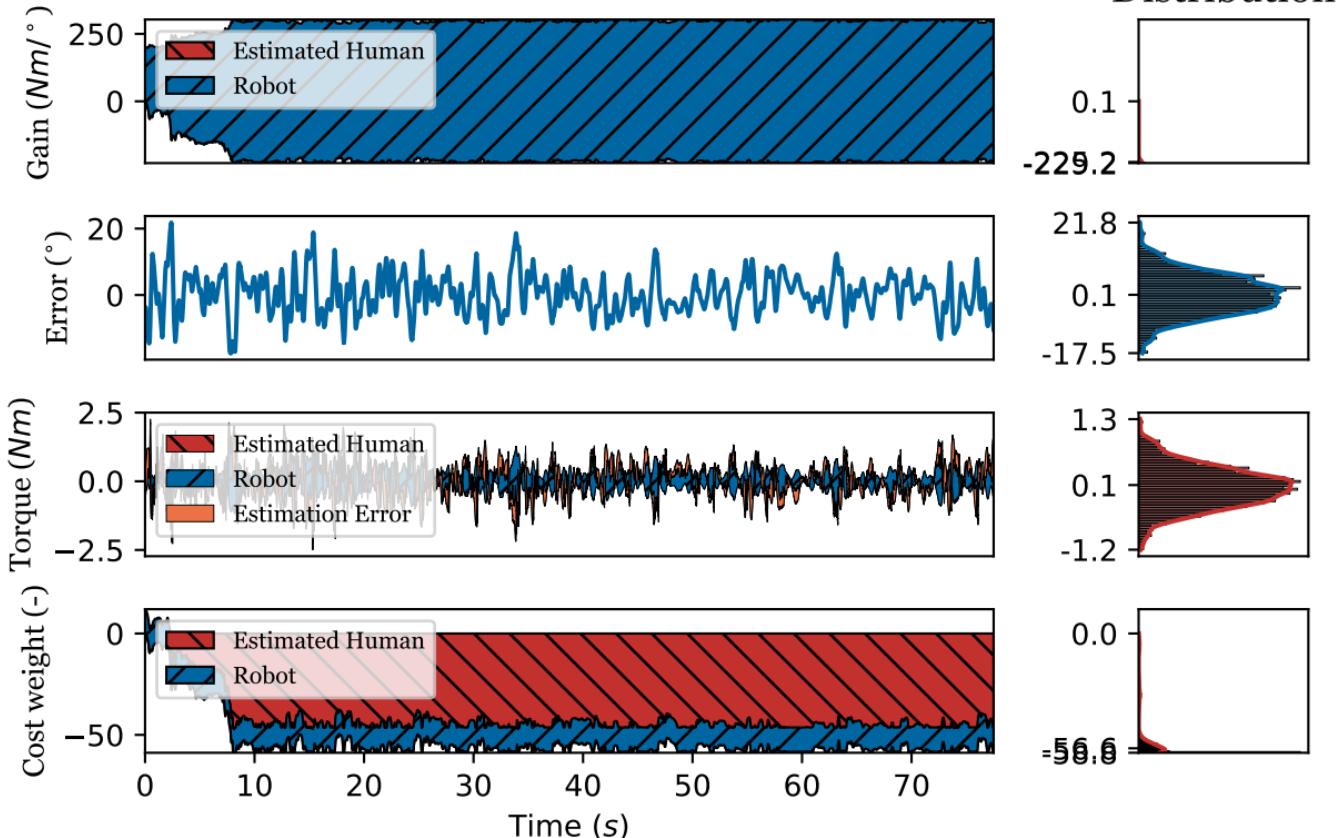
Manual

Positive re.

Negative re.

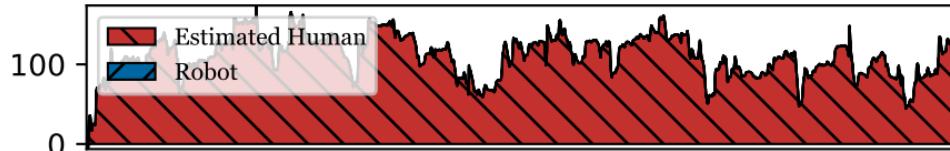


Negative Reinforcement



Manual Control

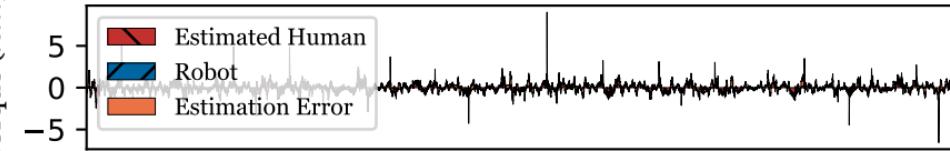
Gain ($Nm/\text{°}$)



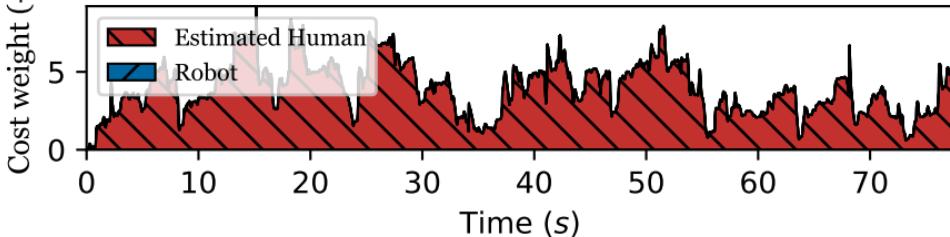
Error (°)



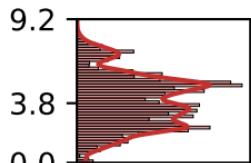
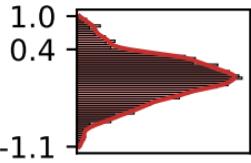
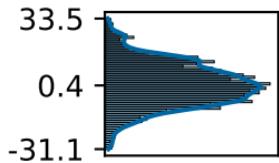
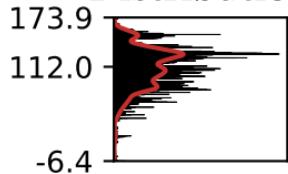
Torque (Nm)



Cost weight (-)



Distribution



Positive Reinforcement

Gain ($Nm/\text{°}$)

100
0

Estimated Human
Robot

Error (°)

50
0

Estimated Human
Robot
Estimation Error

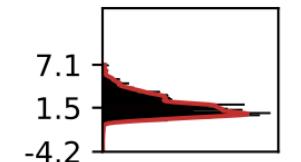
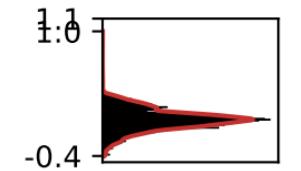
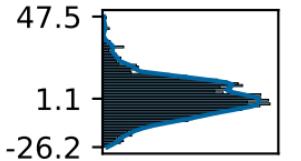
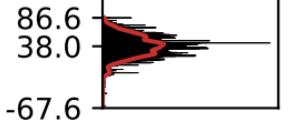
Cost weight (-) Torque (Nm)

10
0

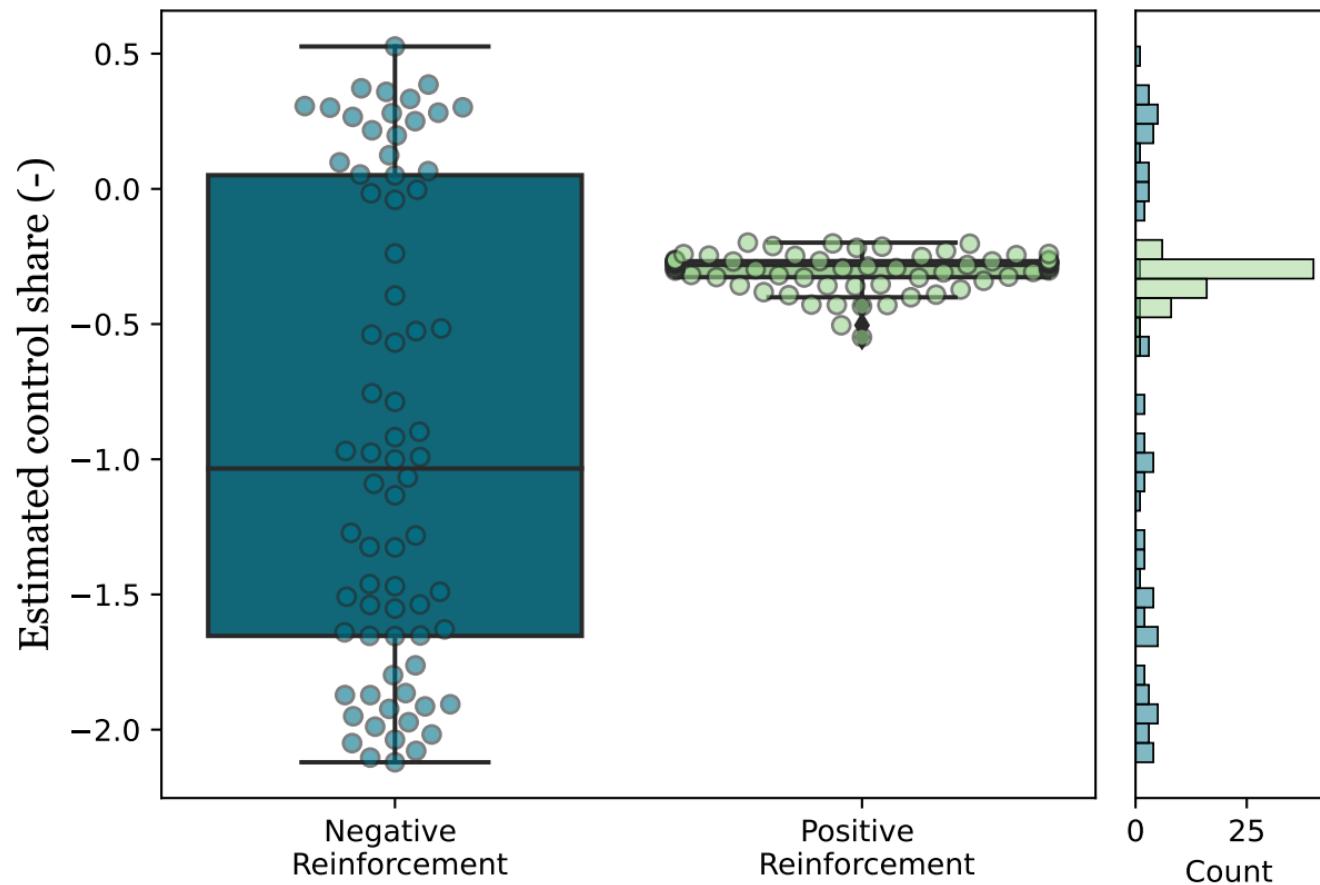
Estimated Human
Robot

Time (s)

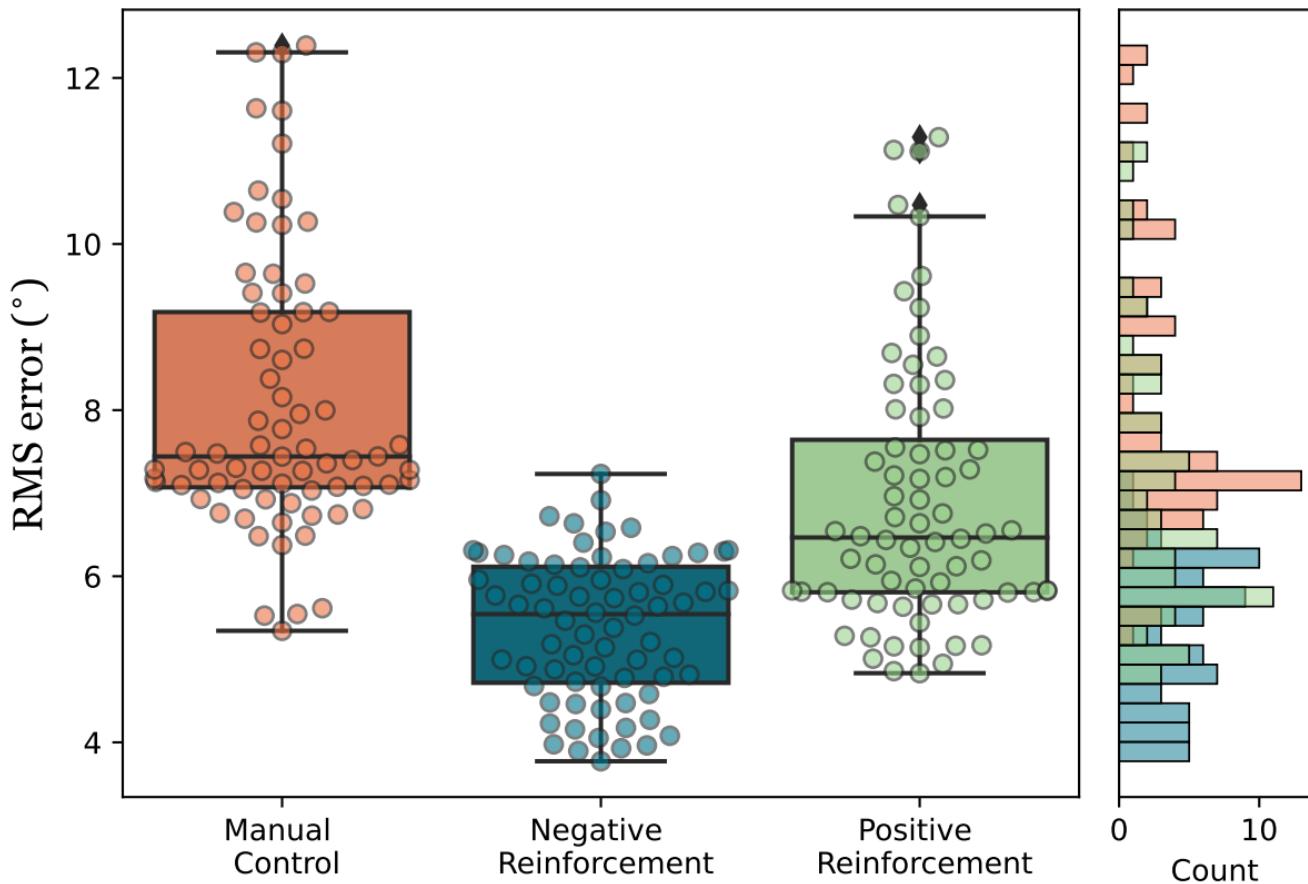
Distribution



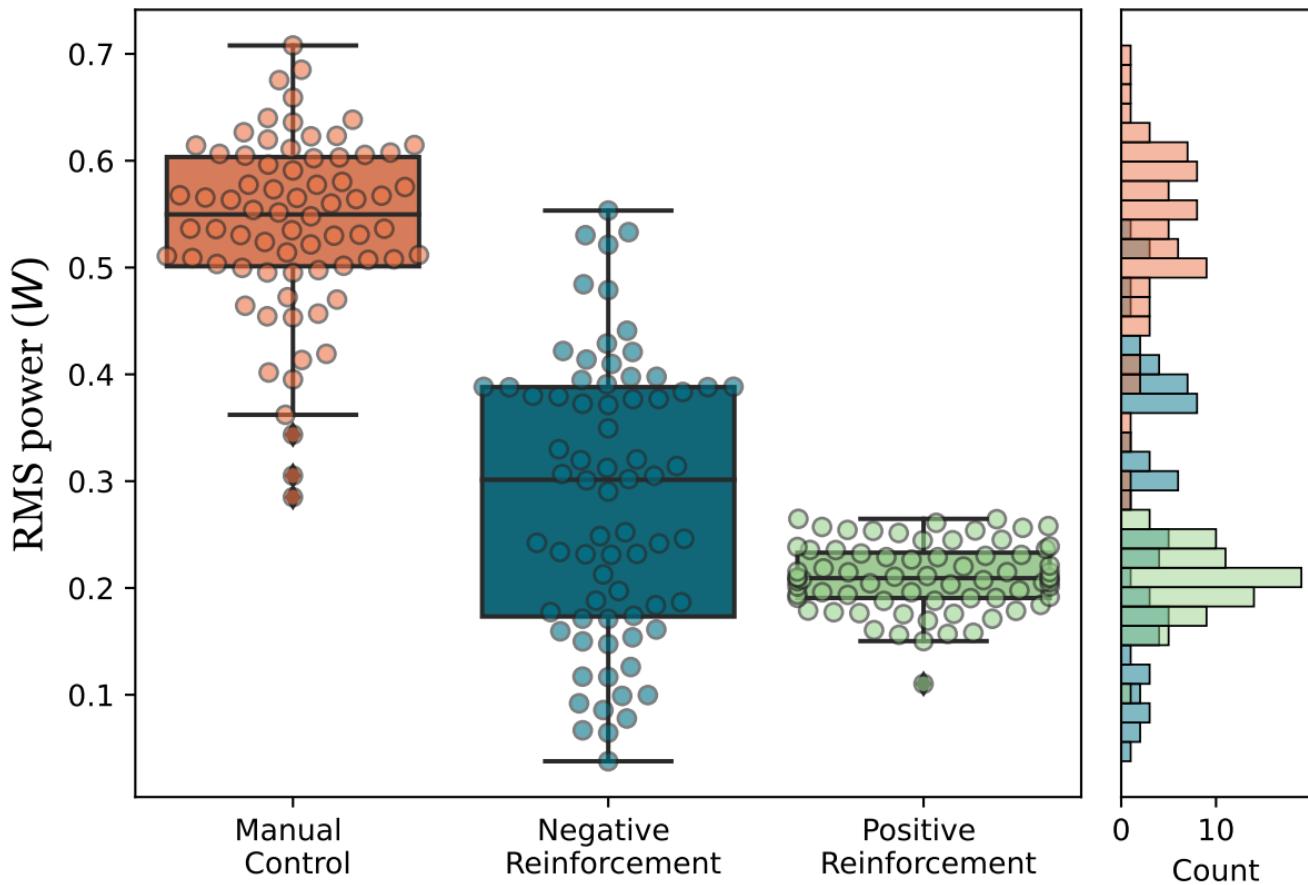
Estimated control Share



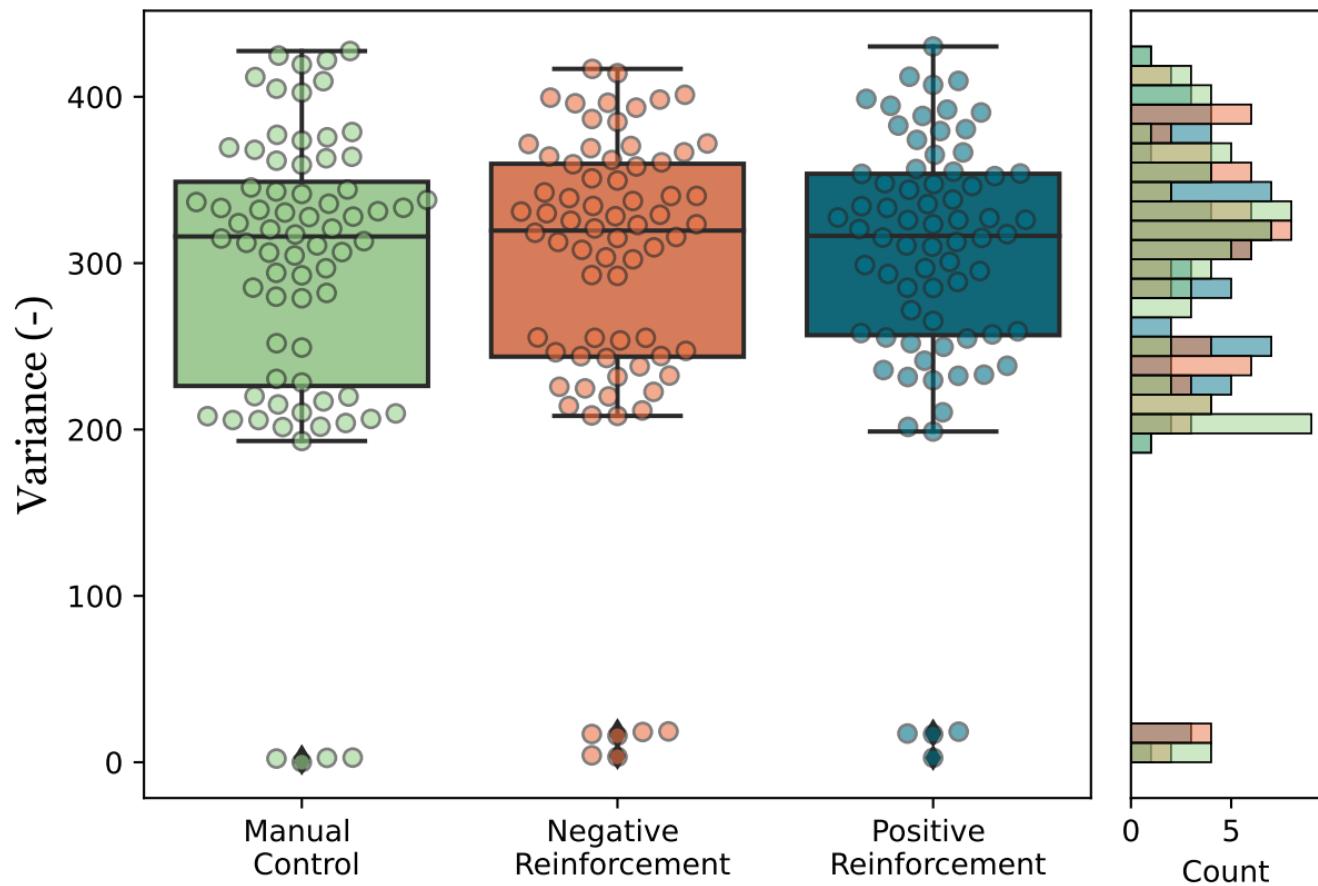
Steering Angle Error



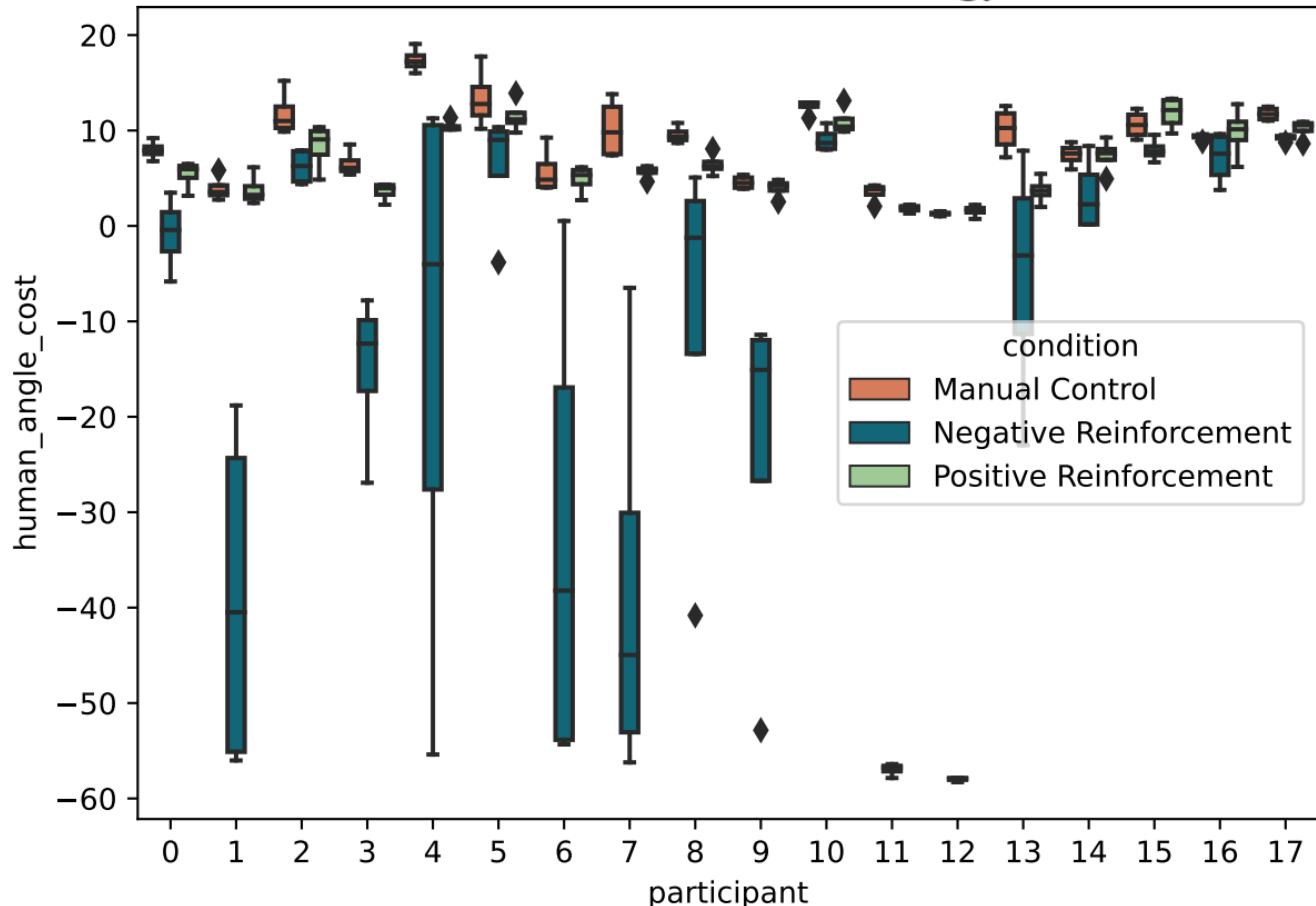
Human Input Power



Cost function variability

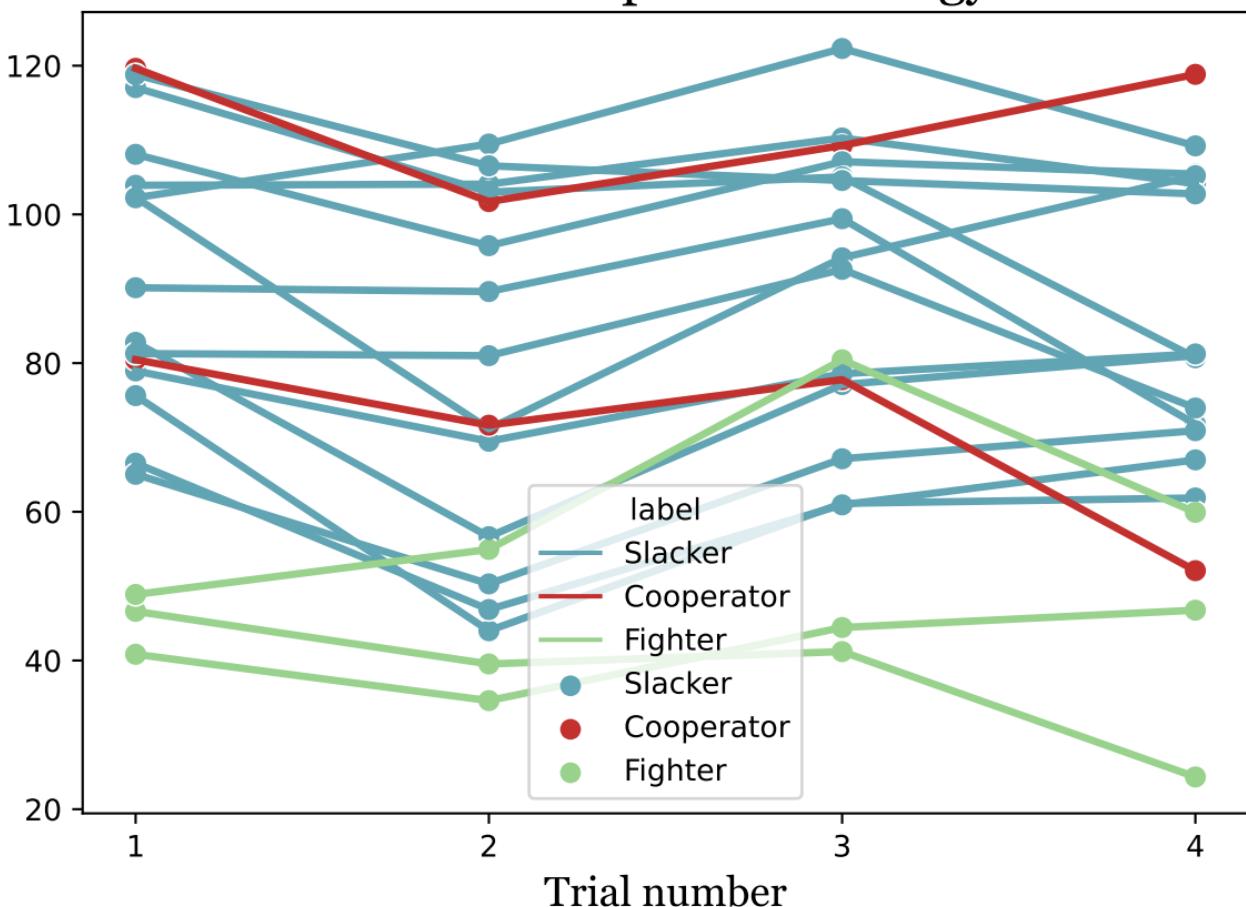


Human control strategy



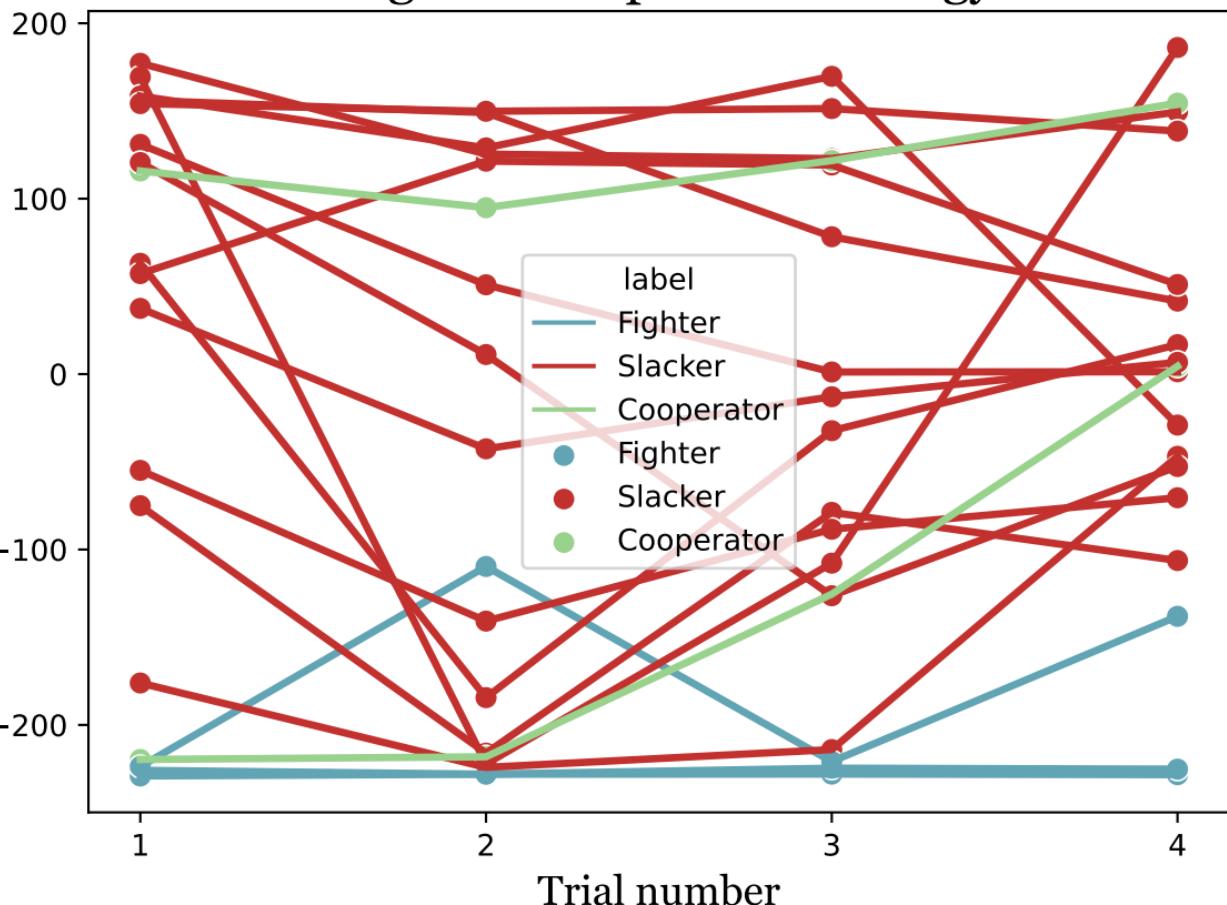
Positive adaptation strategy

Human steering angle gain ($Nm/\text{°}$)

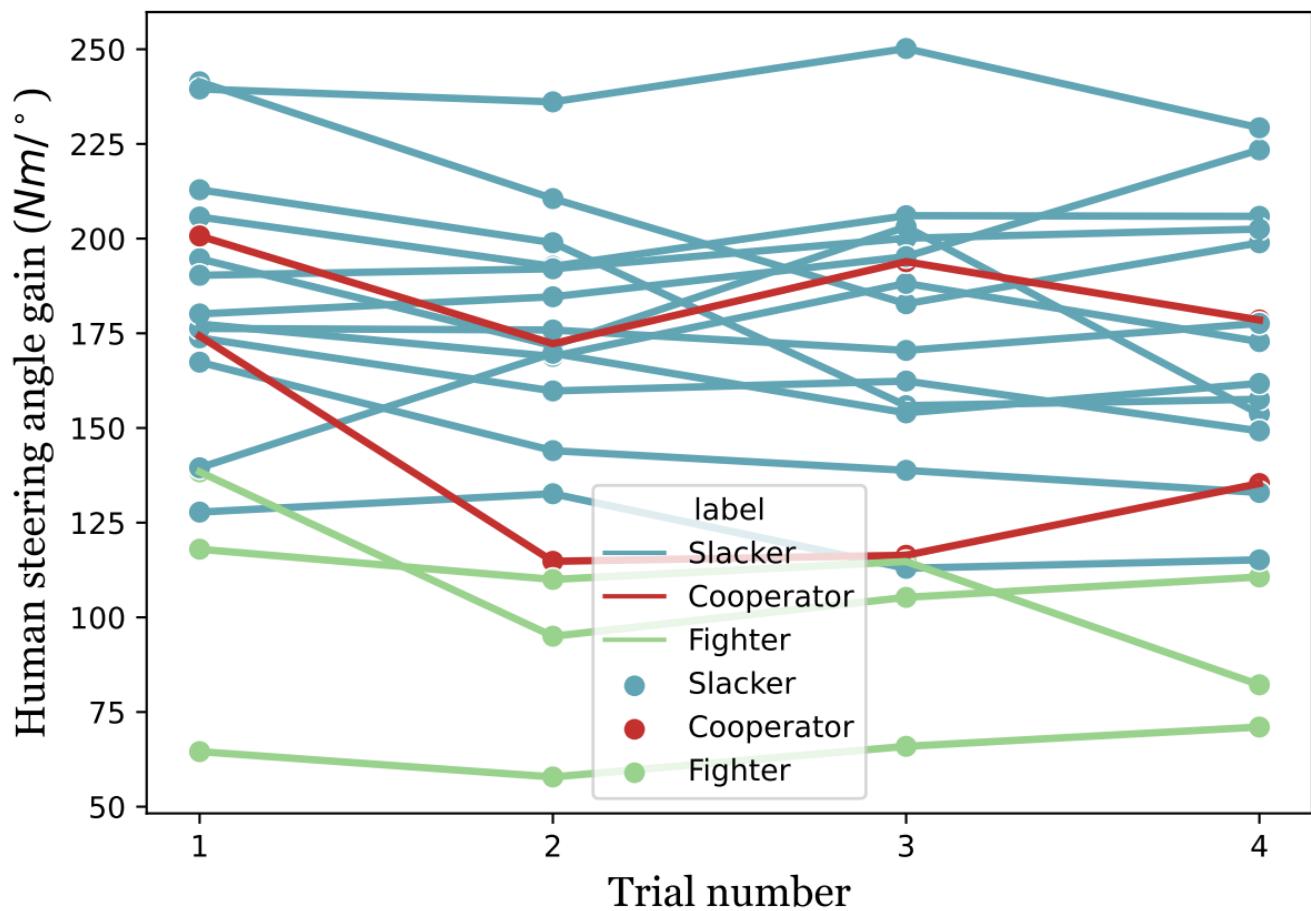


Negative adaptation strategy

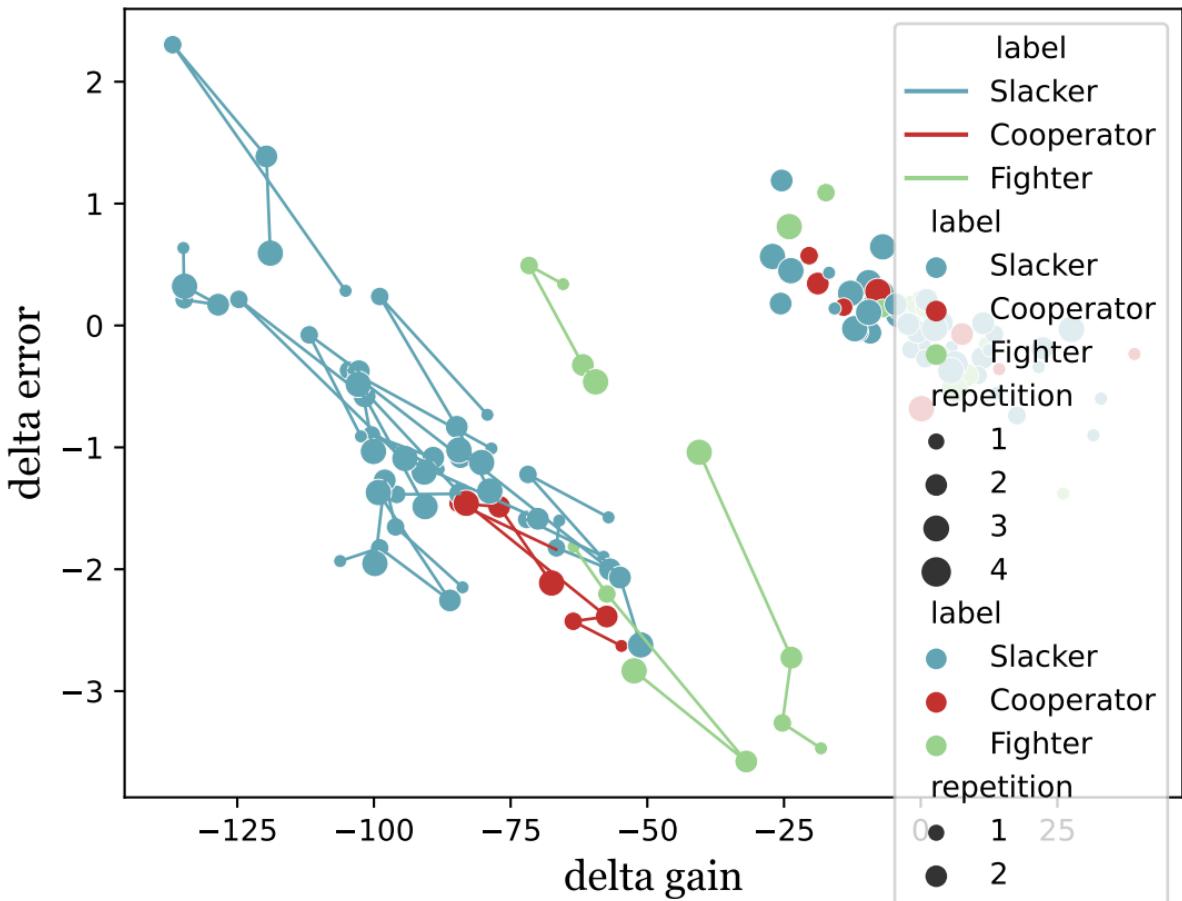
Human steering angle gain ($Nm/\text{ }^\circ$)



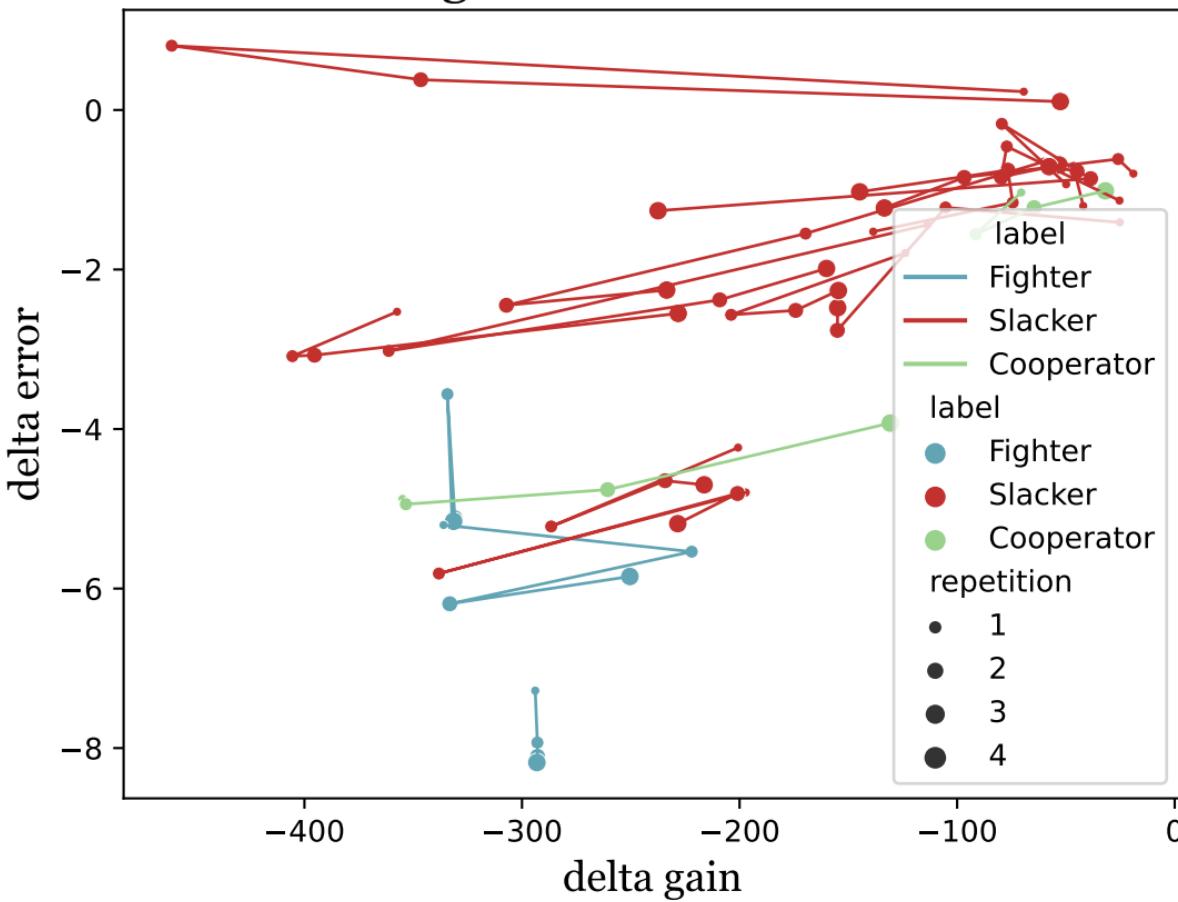
Manual control



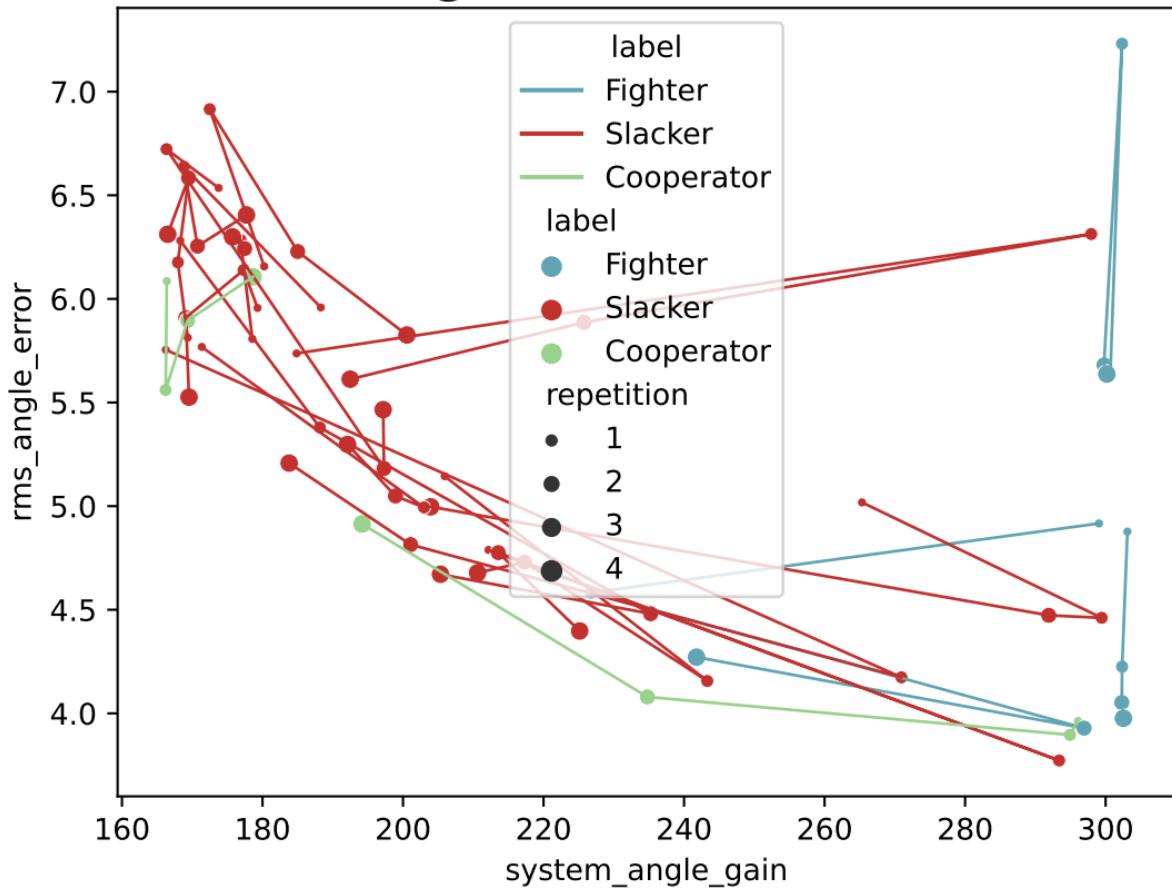
Positive reinforcement



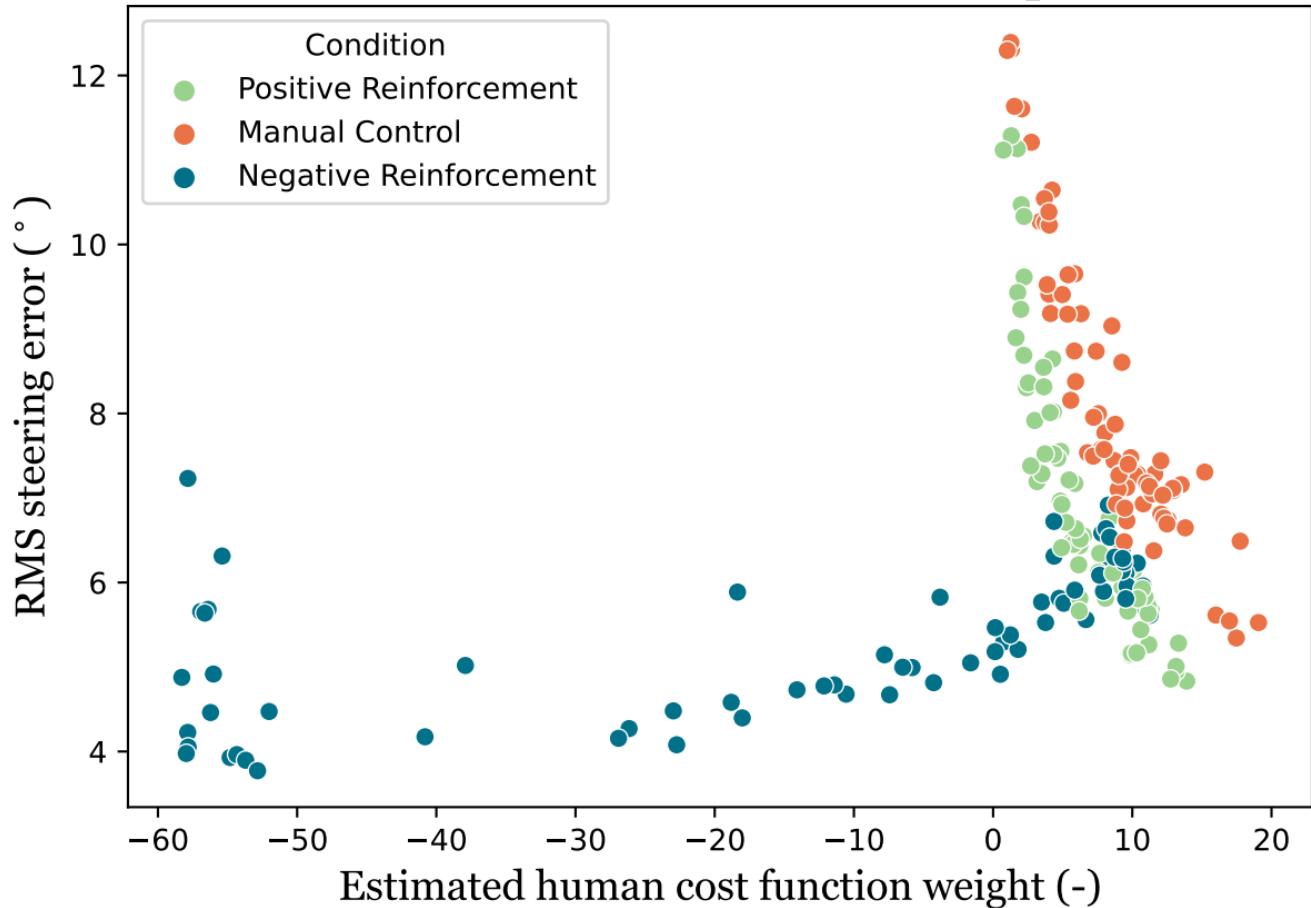
Negative reinforcement



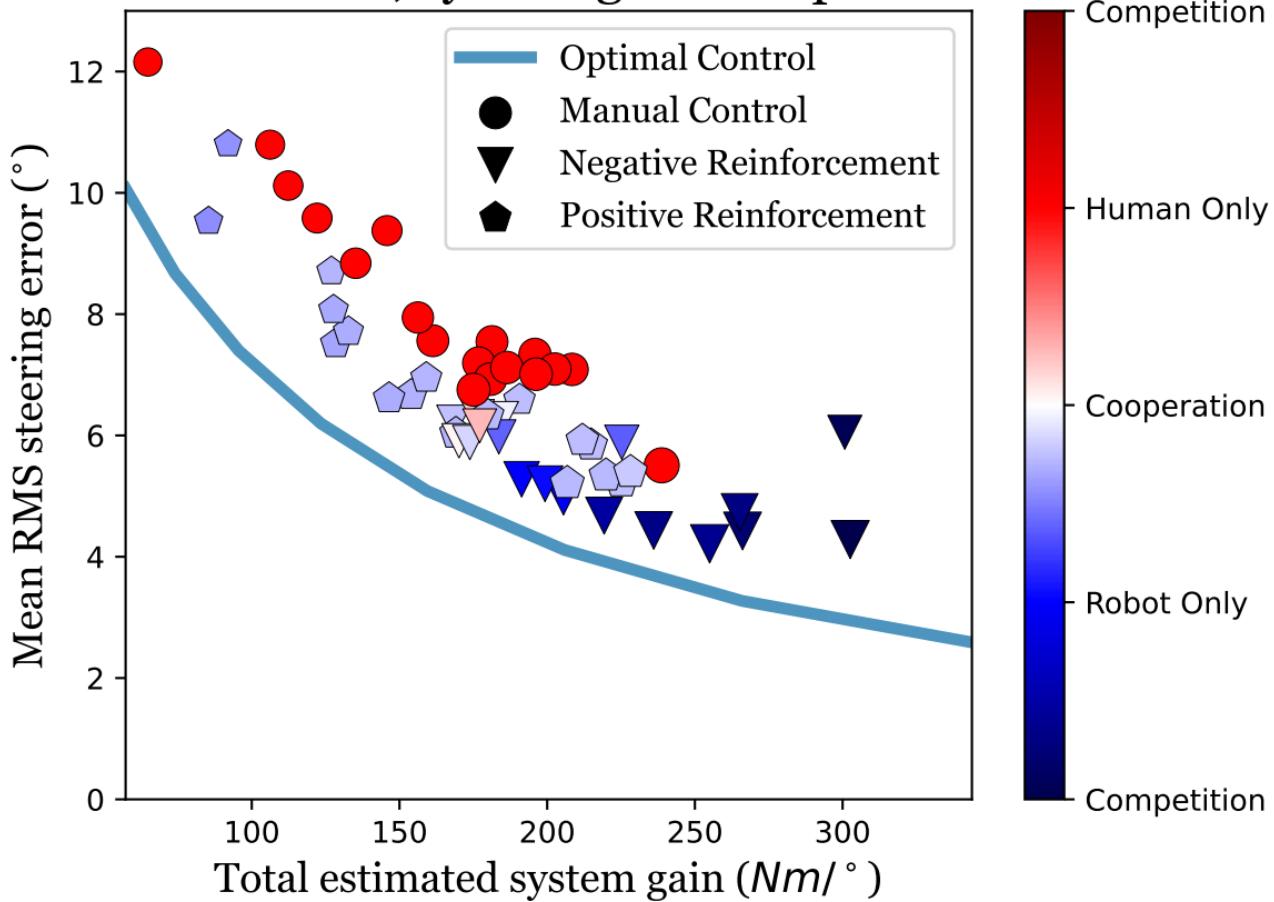
Negative reinforcement



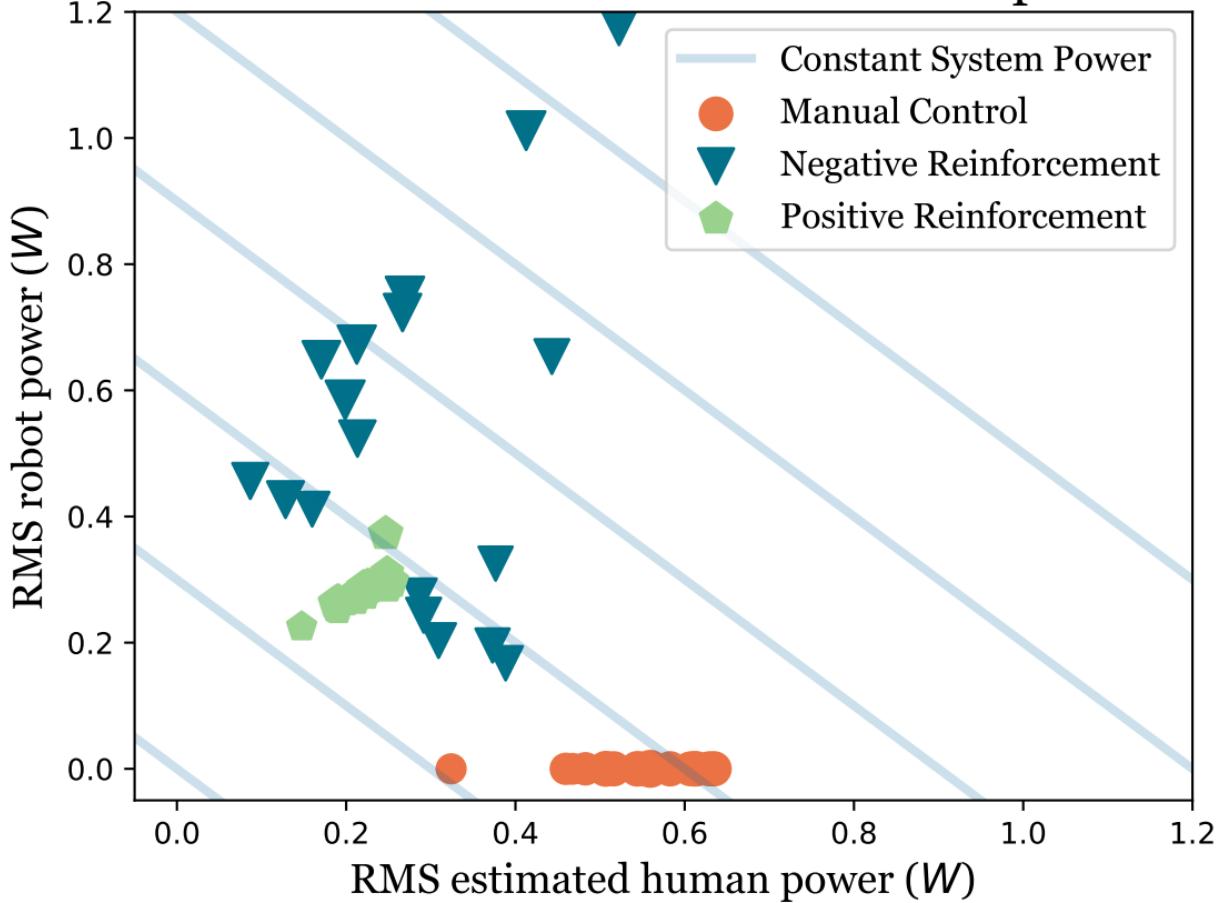
Effect of human cost function on team performance



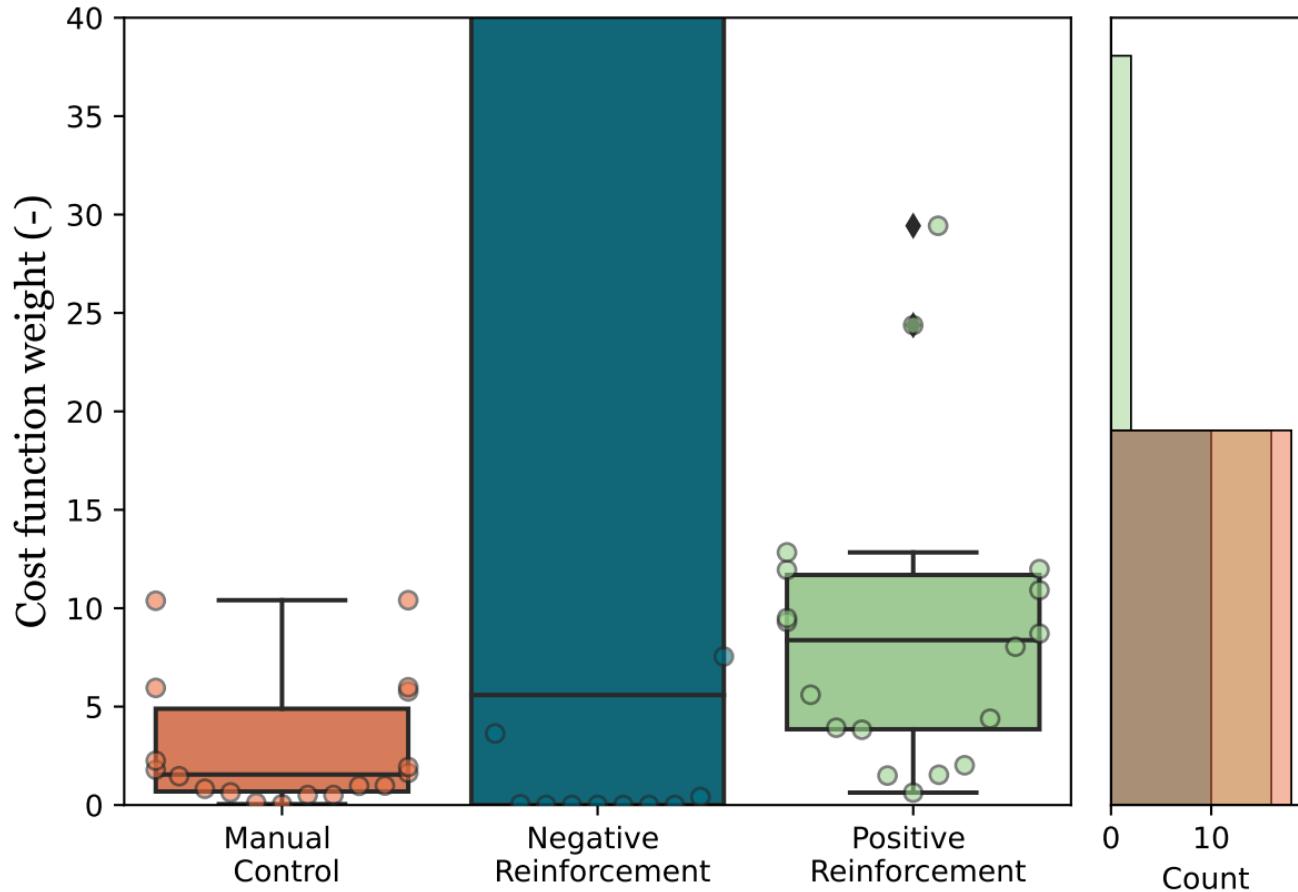
Interaction mode, system gain and performance



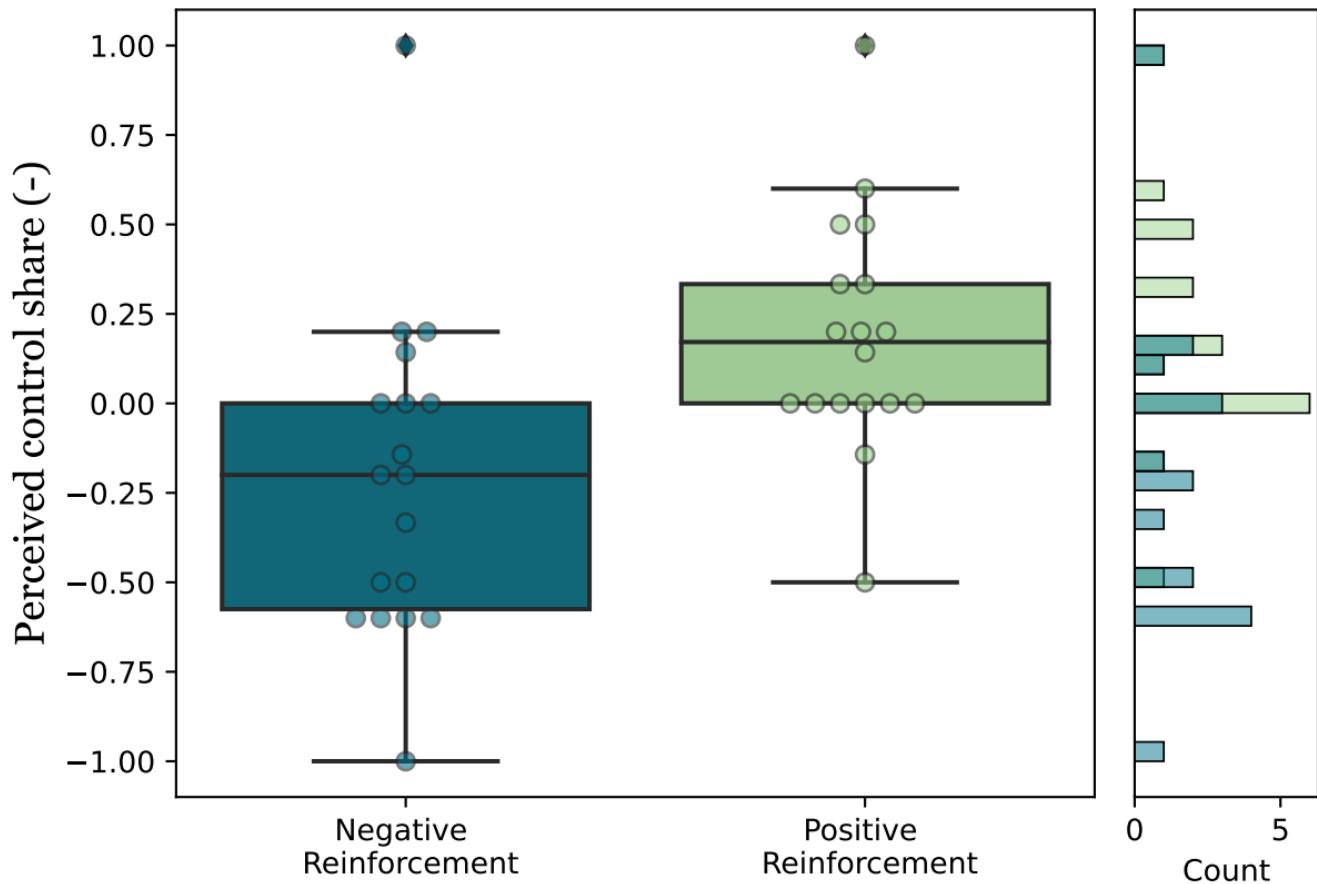
Relation between human and robot power



Trial-by-trial variability



Perceived control share



The interaction from two perspectives

