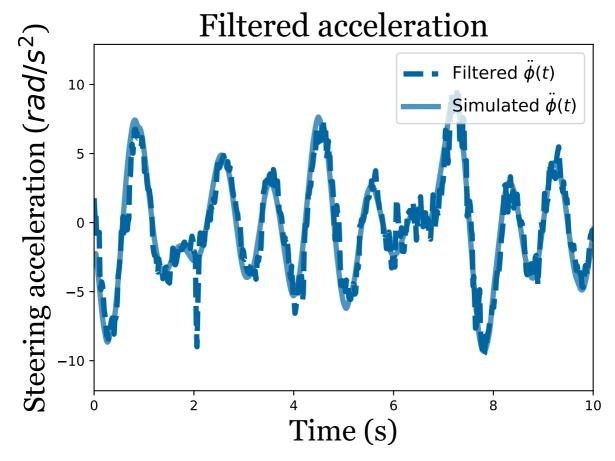
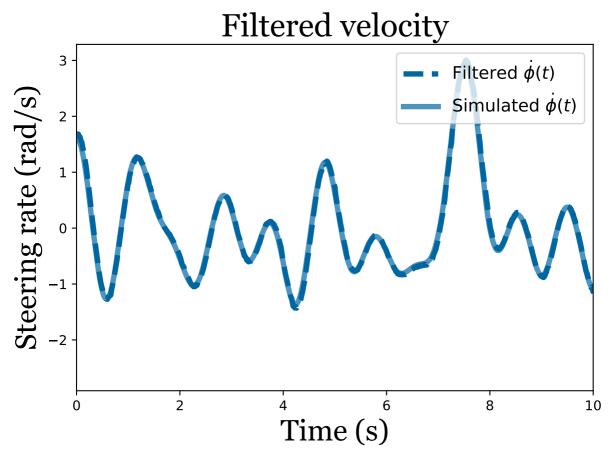


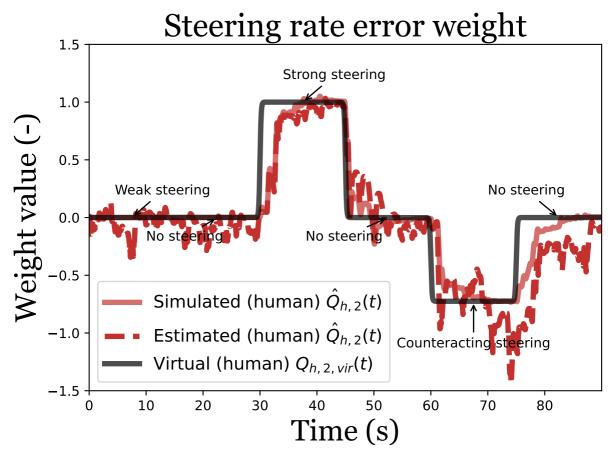
Measured and estimated steering angle Reference $\phi_r(t)$ 1.0 Steering angle $\phi(t)$ Steering angle (rad) Simulated $\phi_{sim}(t)$ 0.5 Estimated $\phi(t)$ 0.0 -0.5 -1.010 Time (s)

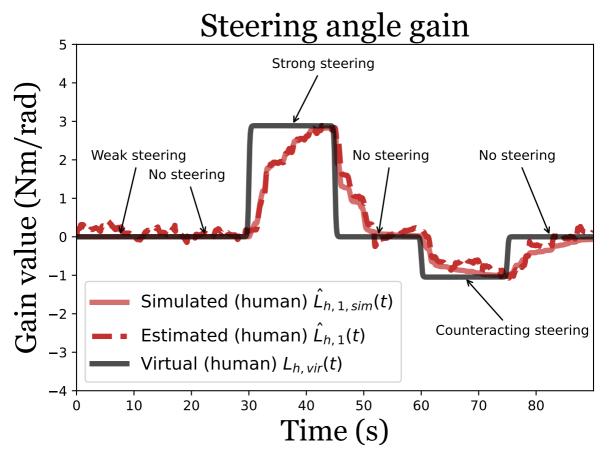


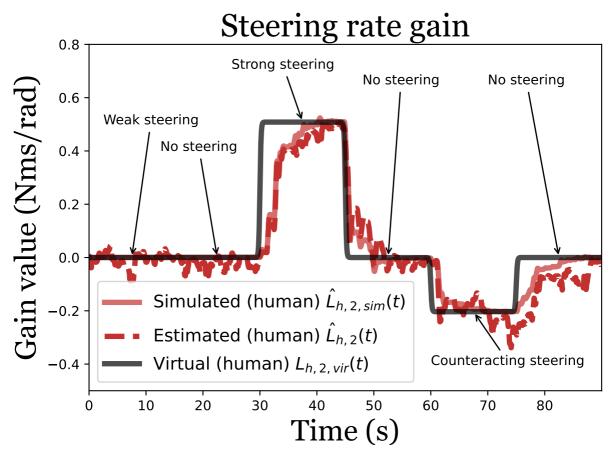


Measured and estimated steering rate 3 Steering angle (rad) Reference $\phi_r(t)$ Steering rate $\phi(t)$ Simulated $\phi_{sim}(t)$ Estimated $\hat{\phi}(t)$ 10 Time (s)

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

