











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

Steering angle error weight Strong action 30 12414 20 Weight value (-) Weak action 10 No interaction No interaction 0 No interaction -10Simulated (human) $\hat{Q}_{h,1}(t)$ Counteracting steering Estimated (human) $Q_{h,1}(t)$ -20 Virtual (human) $Q_{h, 1, vir}(t)$ -3010 20 30 40 50 60 70 80 Time (s)













