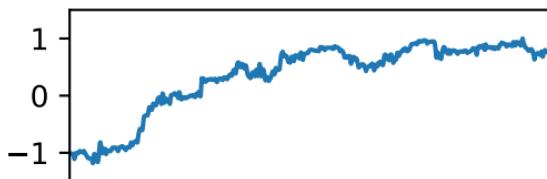
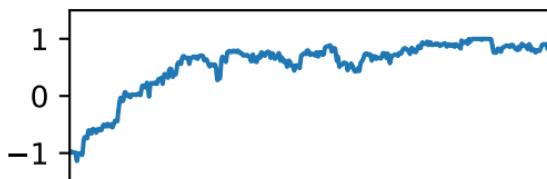
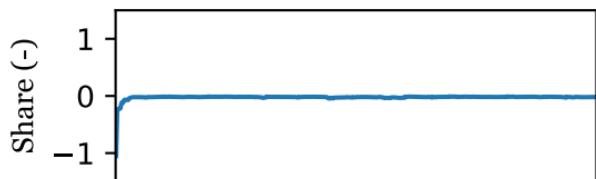
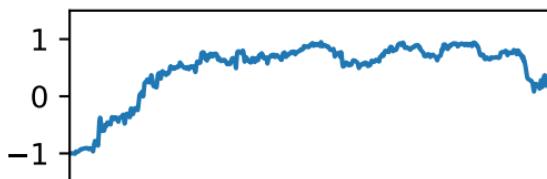
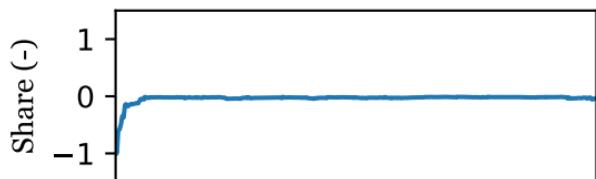
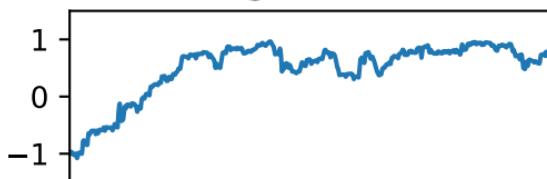


# Estimated Control Share

Positive Re.



Negative Re.

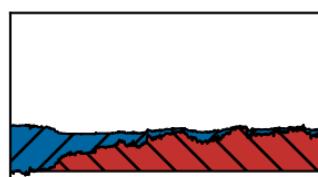
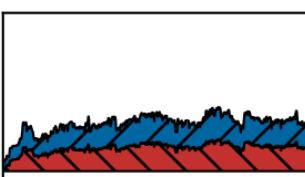
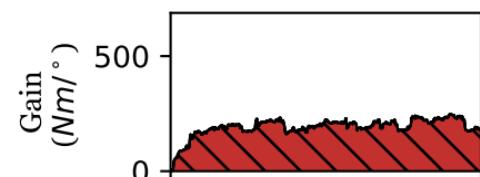
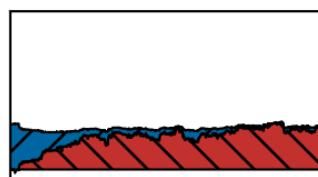
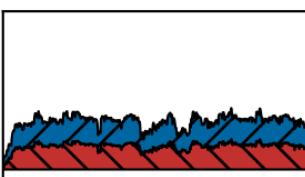
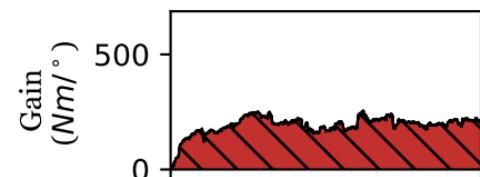
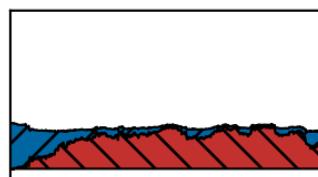
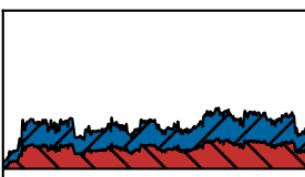
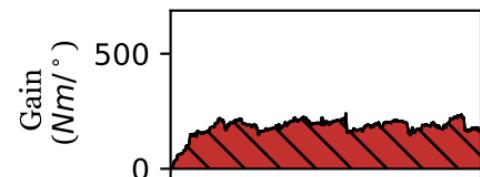
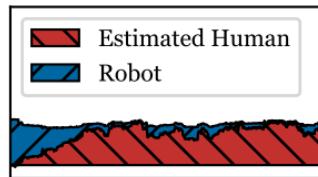
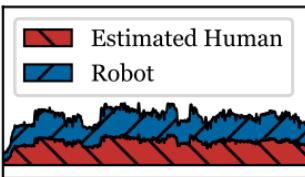
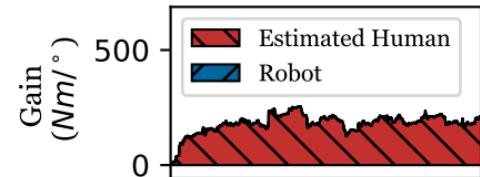


# Controller gain distribution

Manual

Positive Re.

Negative Re.

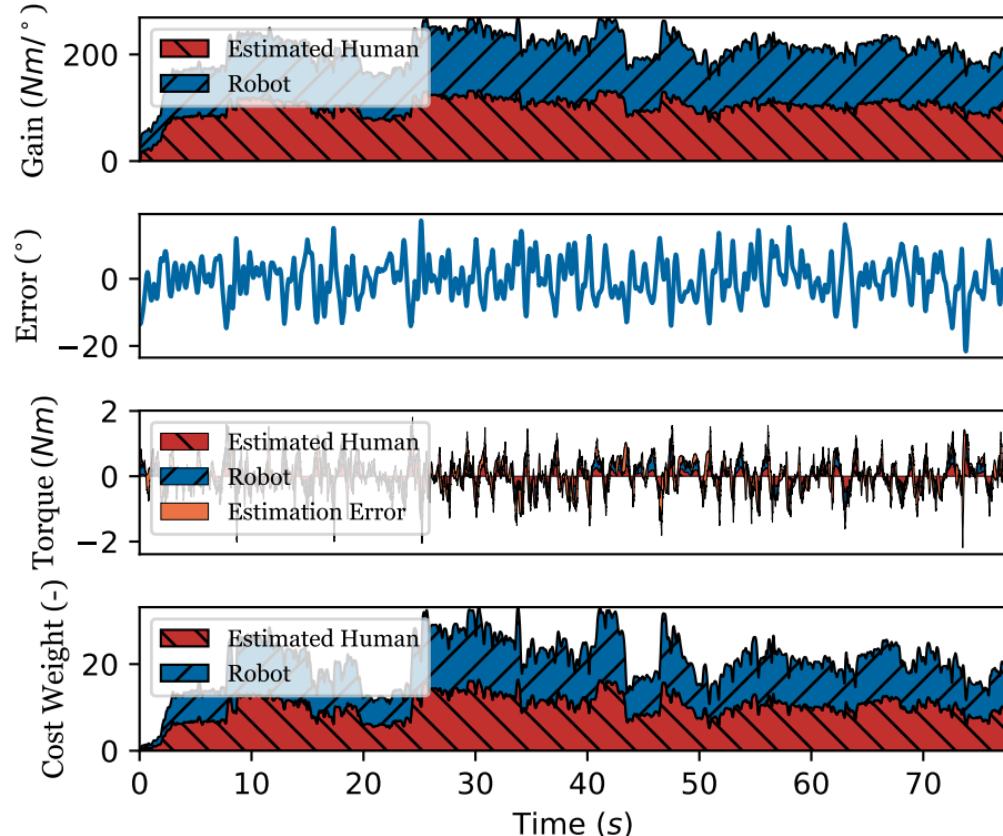


Time (s)

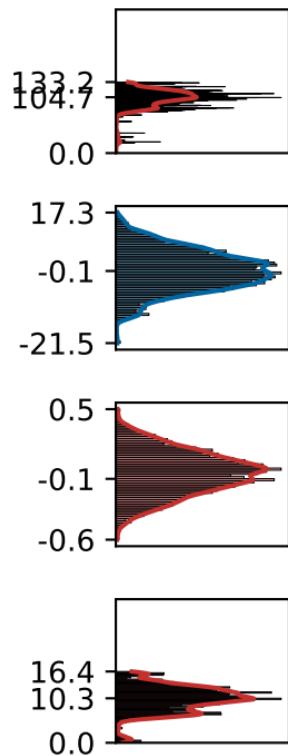
Time (s)

Time (s)

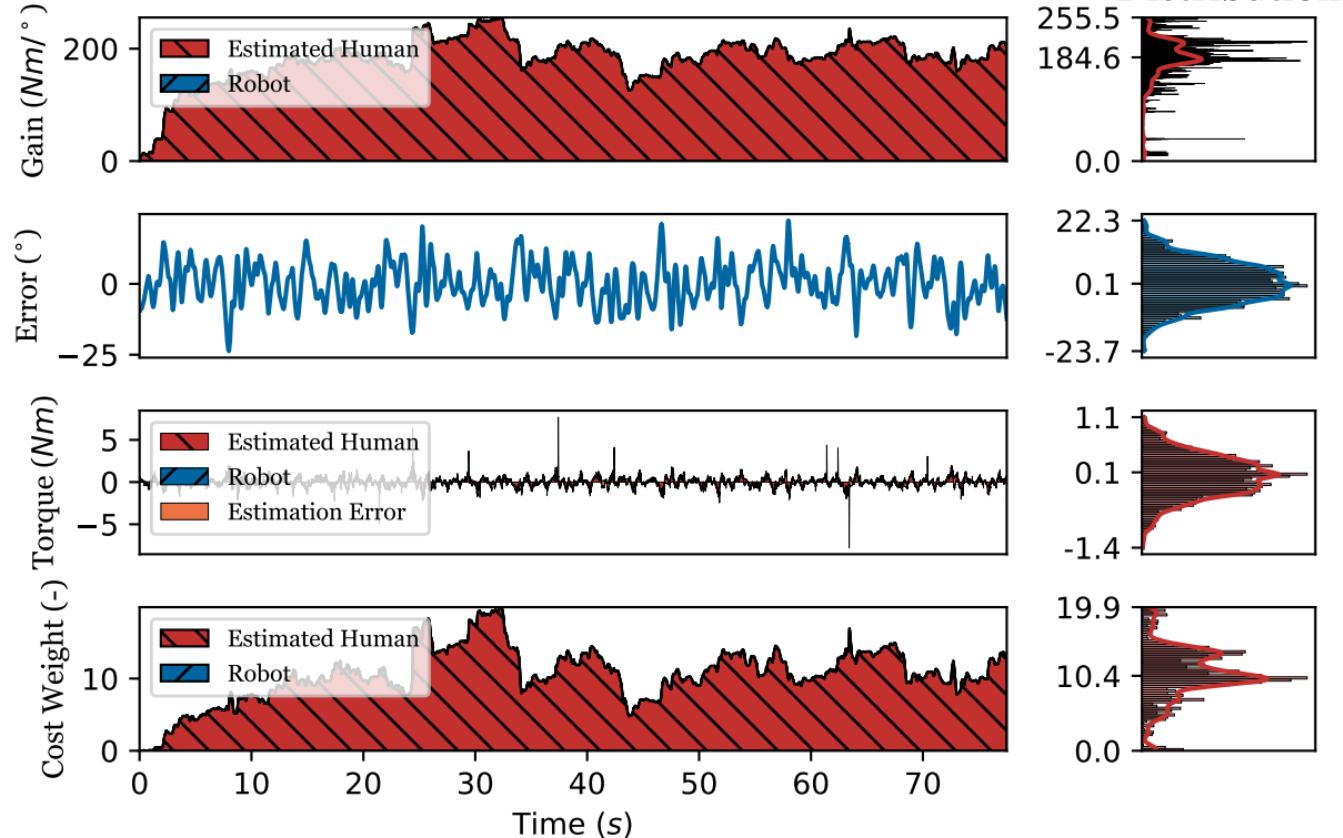
# Positive Reinforcement



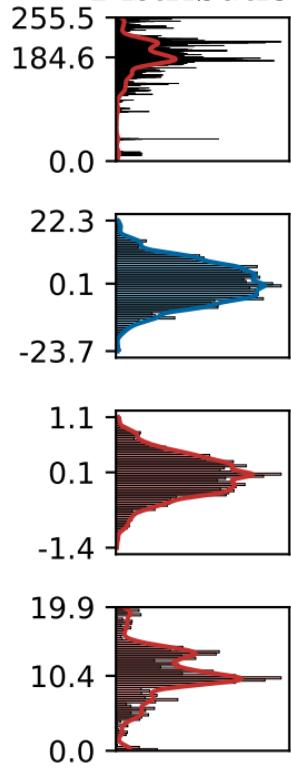
Distribution



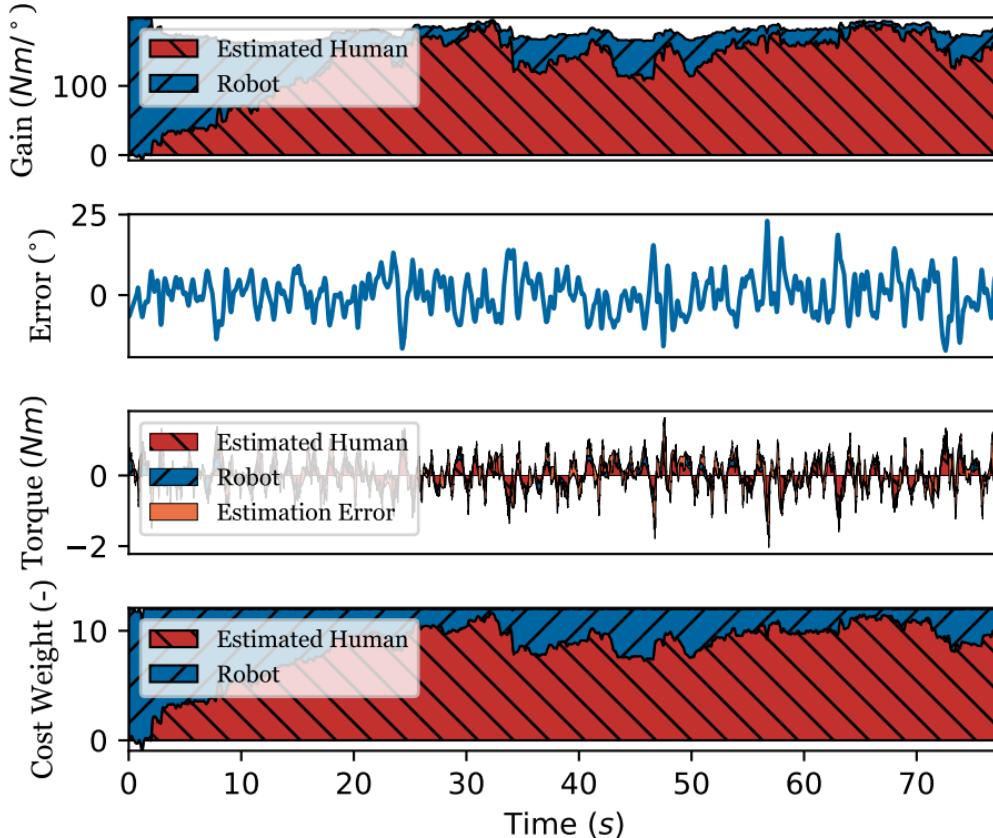
# Manual Control



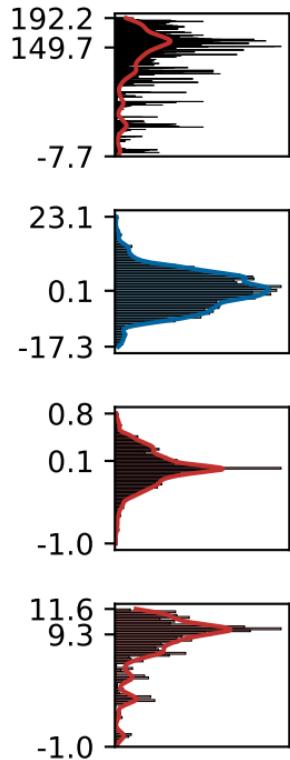
Distribution



# Negative Reinforcement



Distribution

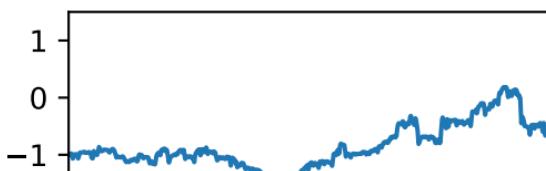
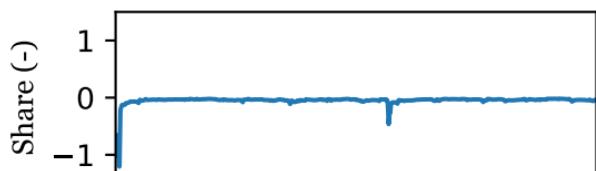
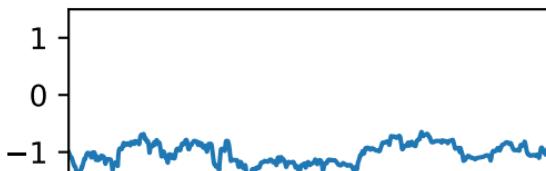
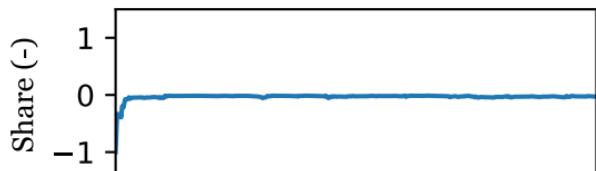
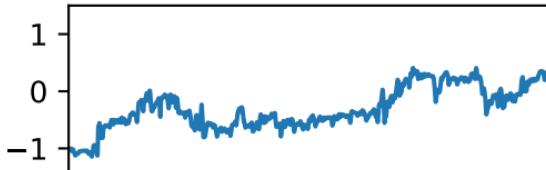
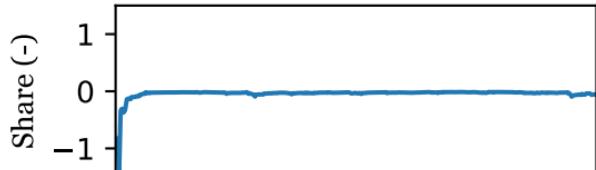
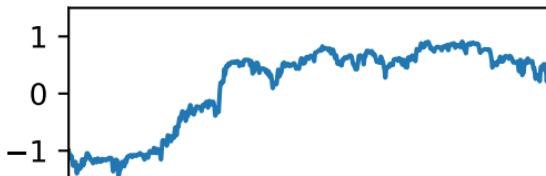


# Estimated Control Share

Positive Re.



Negative Re.



Time (s)

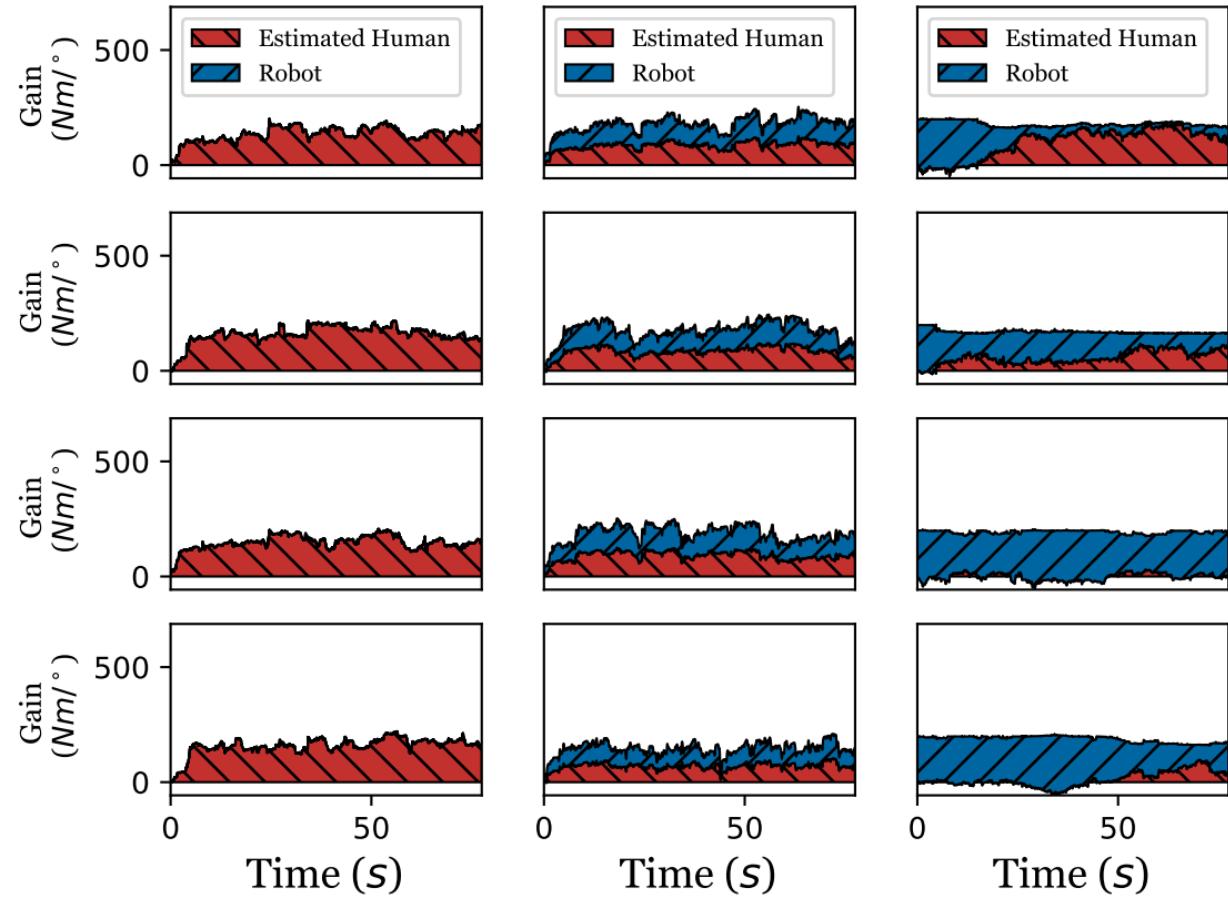
Time (s)

# Controller gain distribution

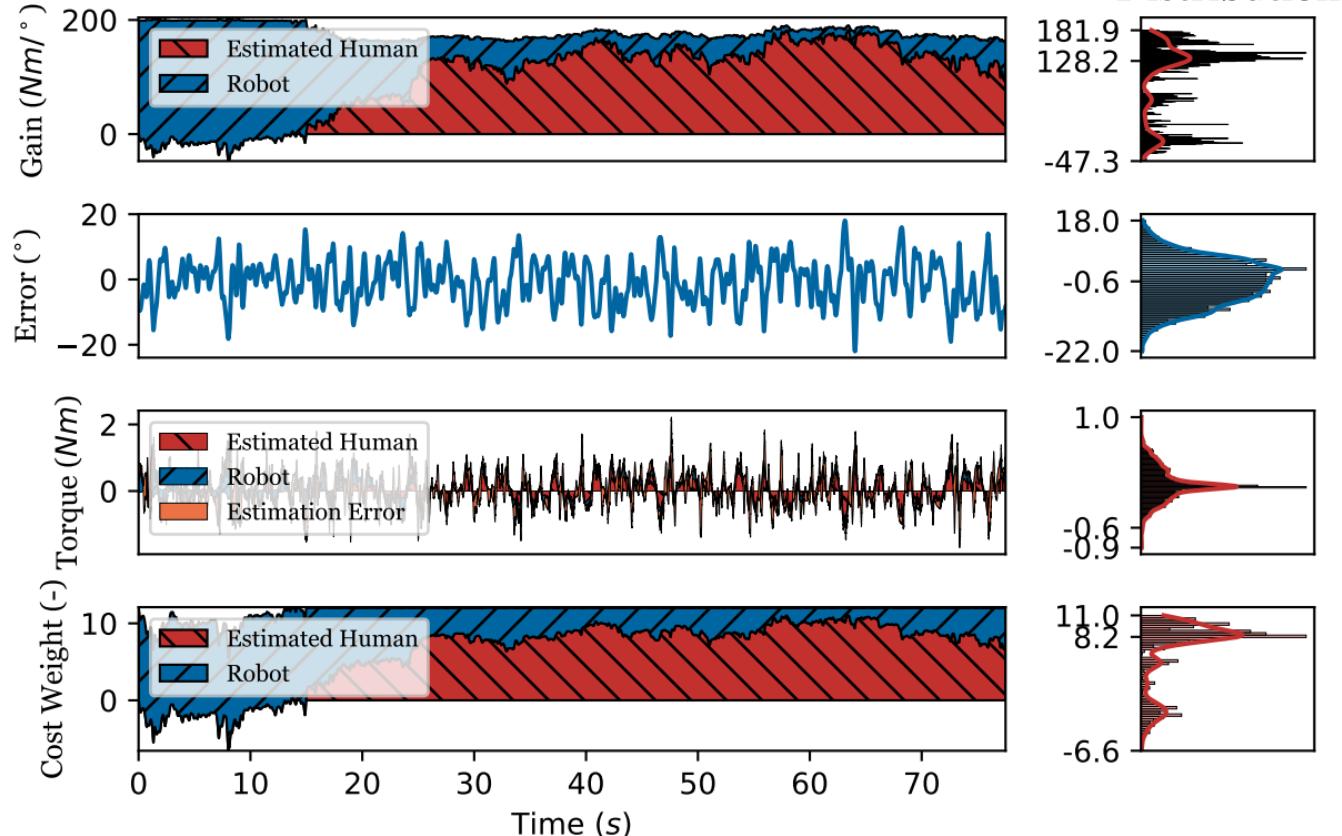
Manual

Positive Re.

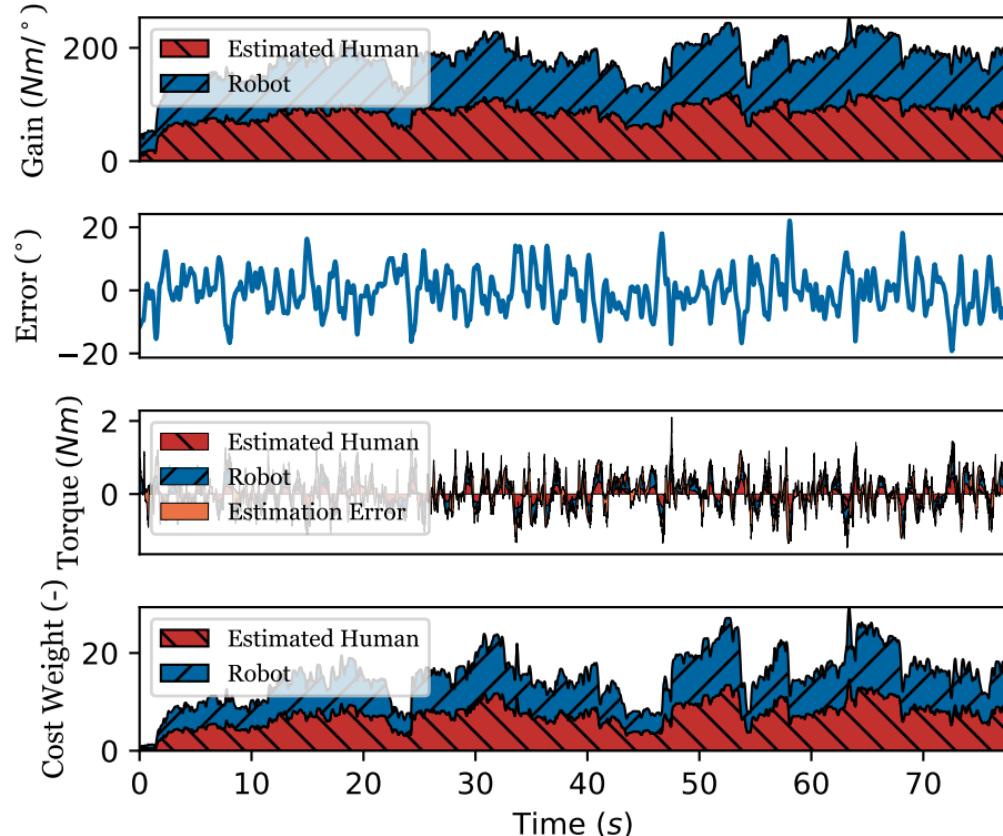
Negative Re.



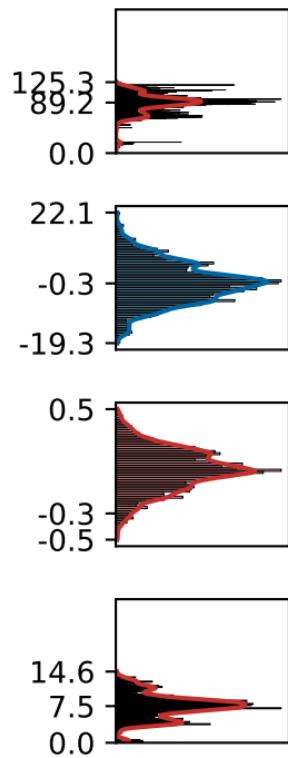
# Negative Reinforcement



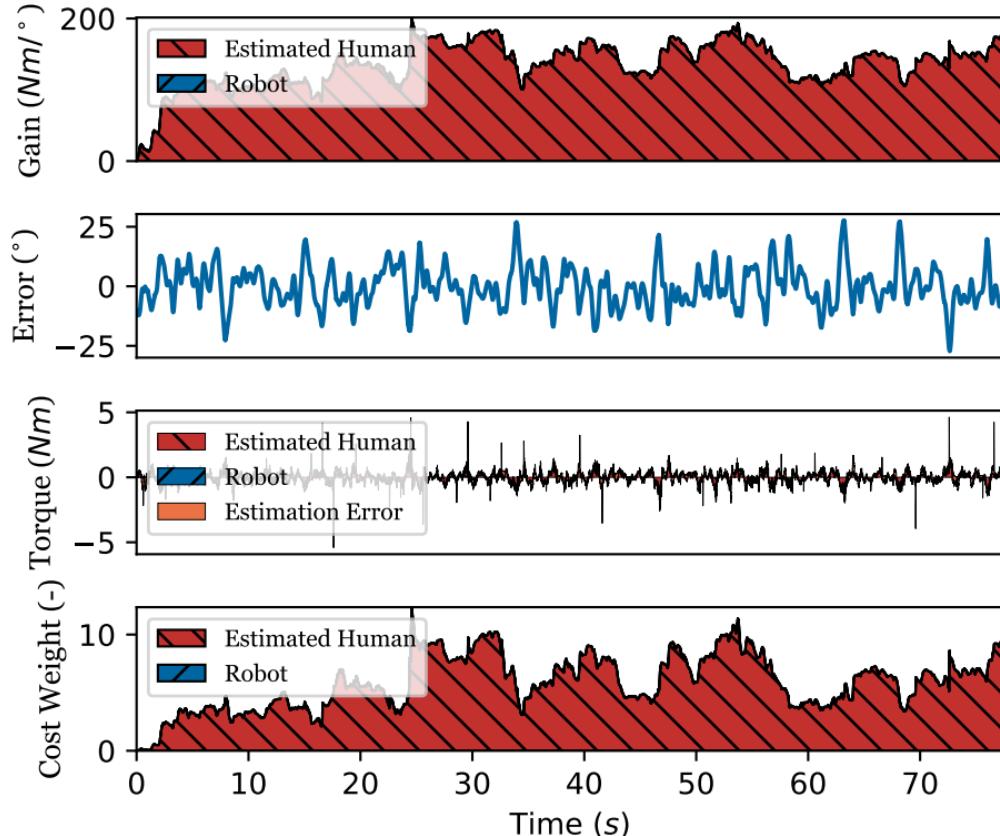
# Positive Reinforcement



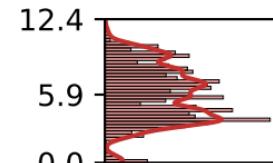
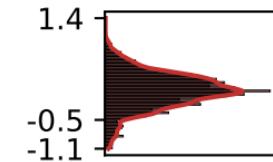
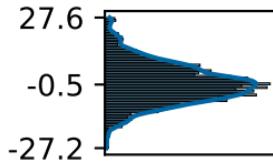
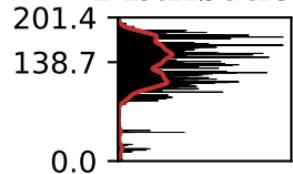
Distribution



# Manual Control

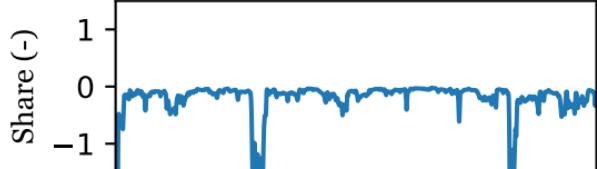


Distribution

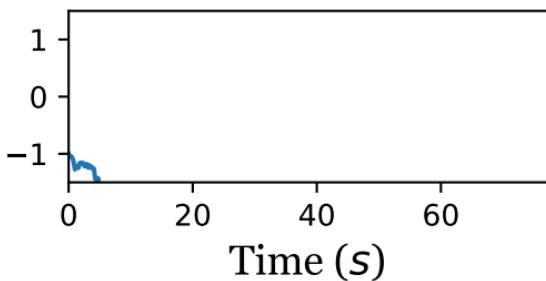
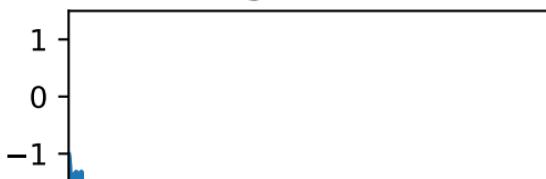
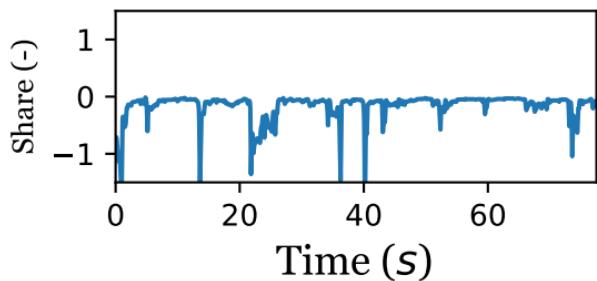
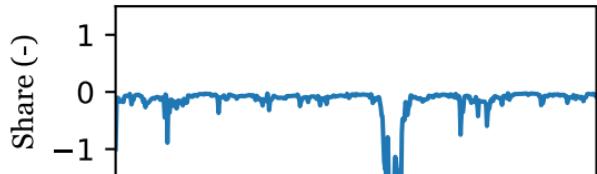
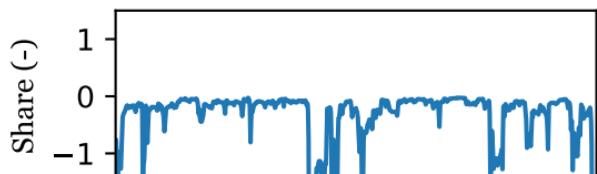


# Estimated Control Share

Positive Re.



Negative Re.

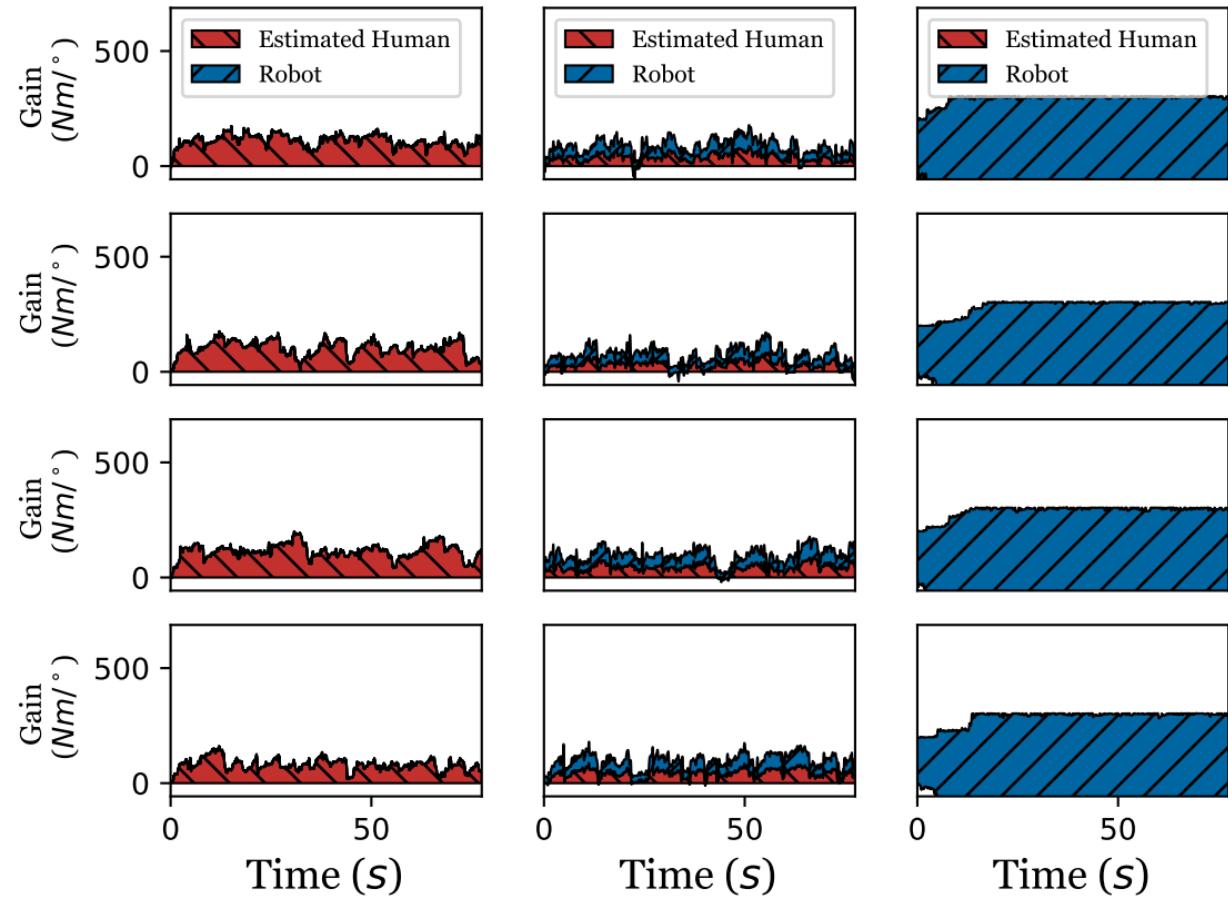


# Controller gain distribution

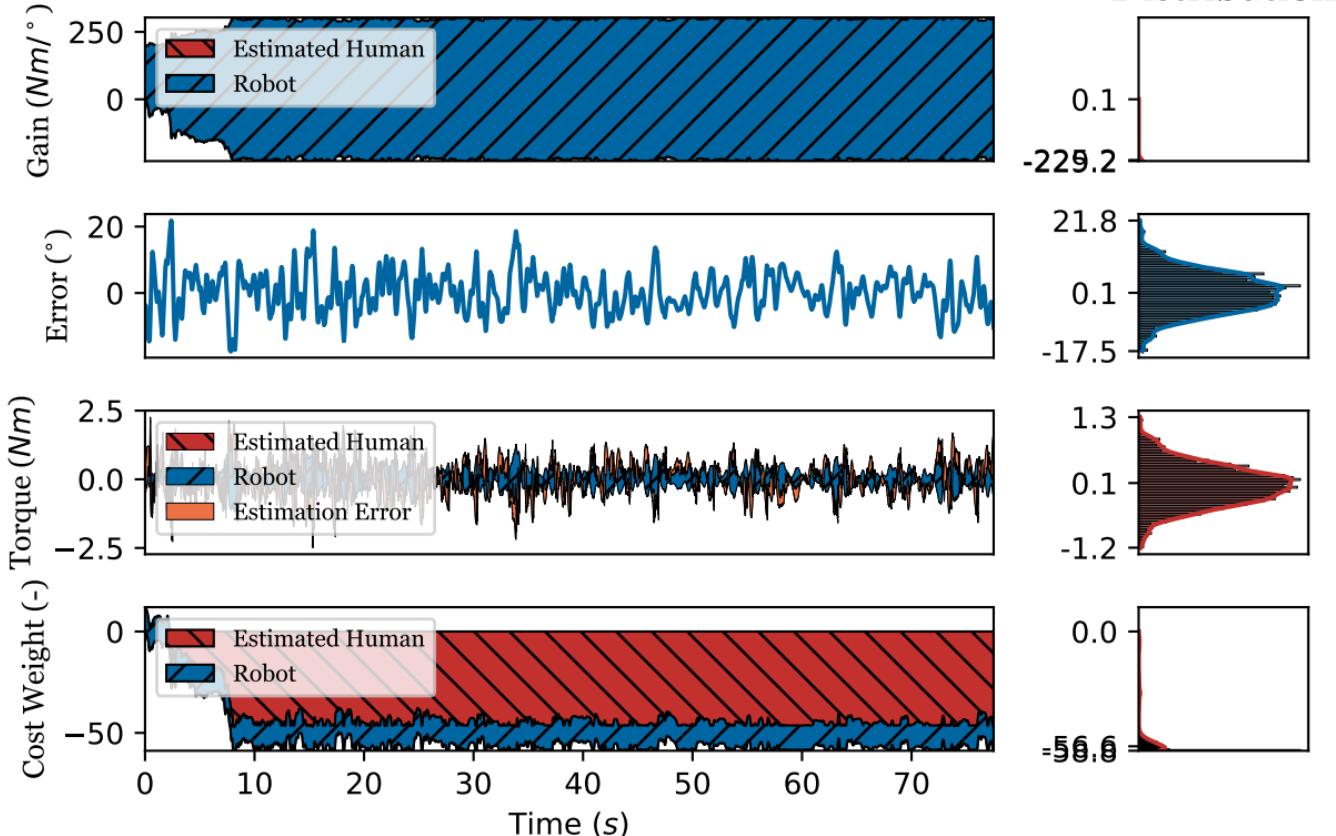
Manual

Positive Re.

Negative Re.

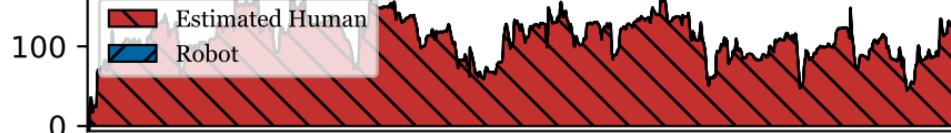


# Negative Reinforcement



# Manual Control

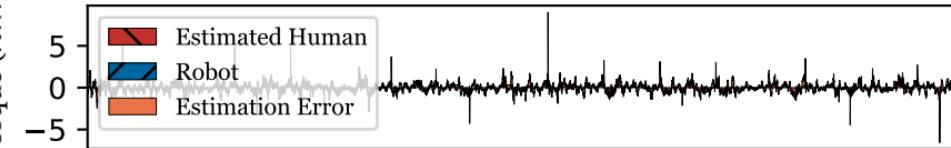
Gain ( $Nm/\text{°}$ )



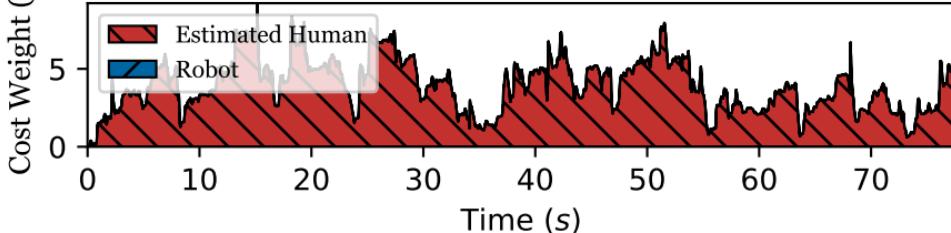
Error (°)



Torque (Nm)

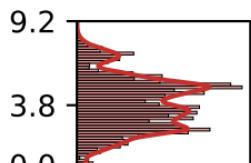
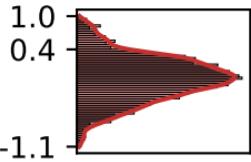
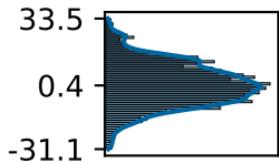
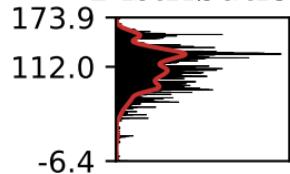


Cost Weight (-)



Time (s)

Distribution



# Positive Reinforcement

Gain ( $Nm/\text{°}$ )

100  
0

Estimated Human  
Robot

Error (°)

50  
0

Estimated Human  
Robot  
Estimation Error

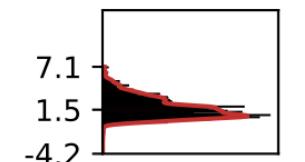
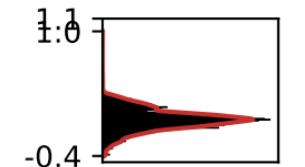
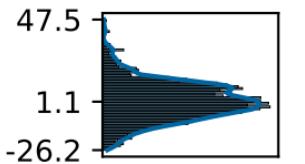
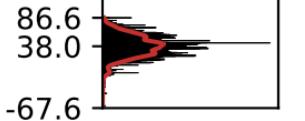
Cost Weight (-) Torque (Nm)

10  
0

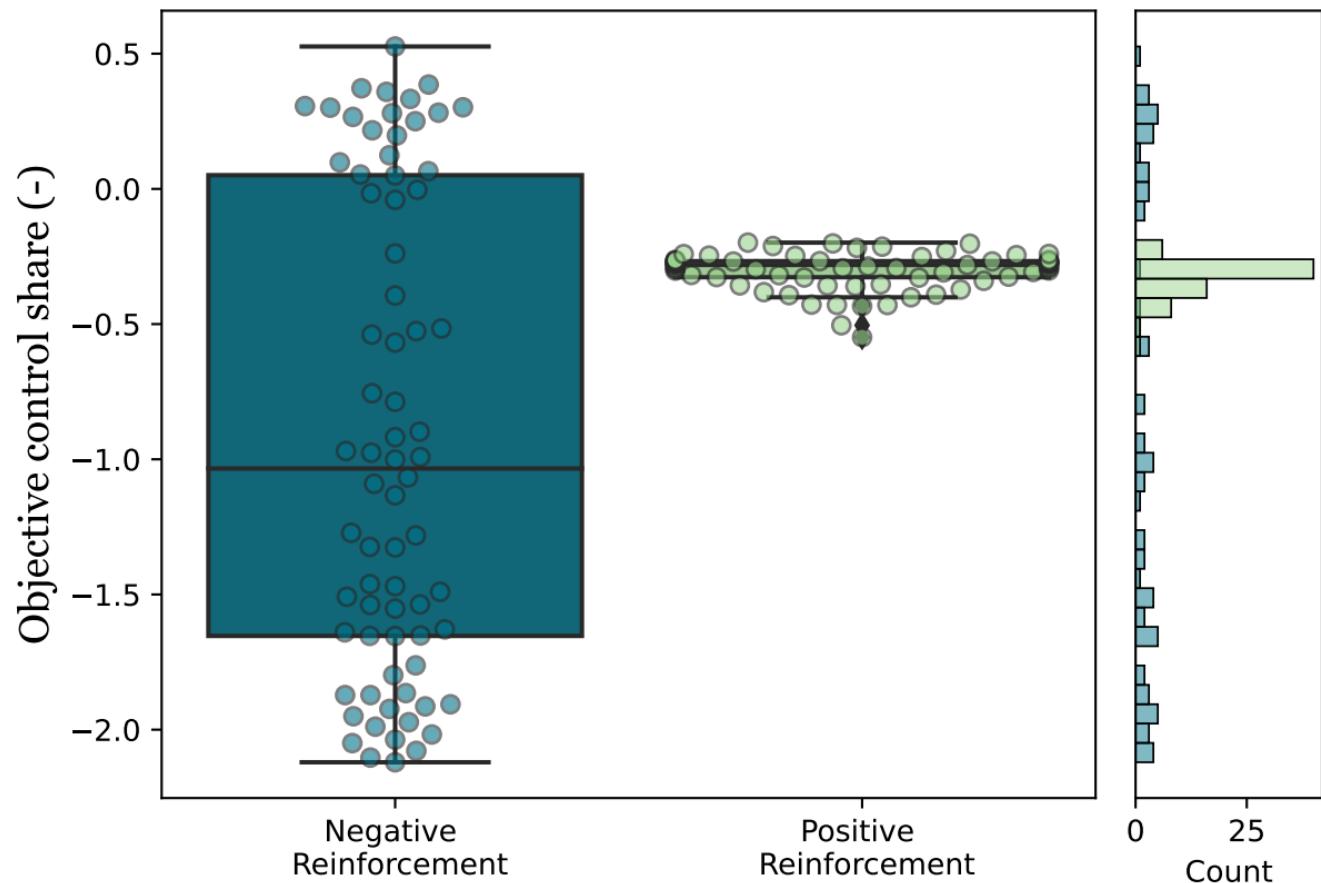
Estimated Human  
Robot

Time (s)

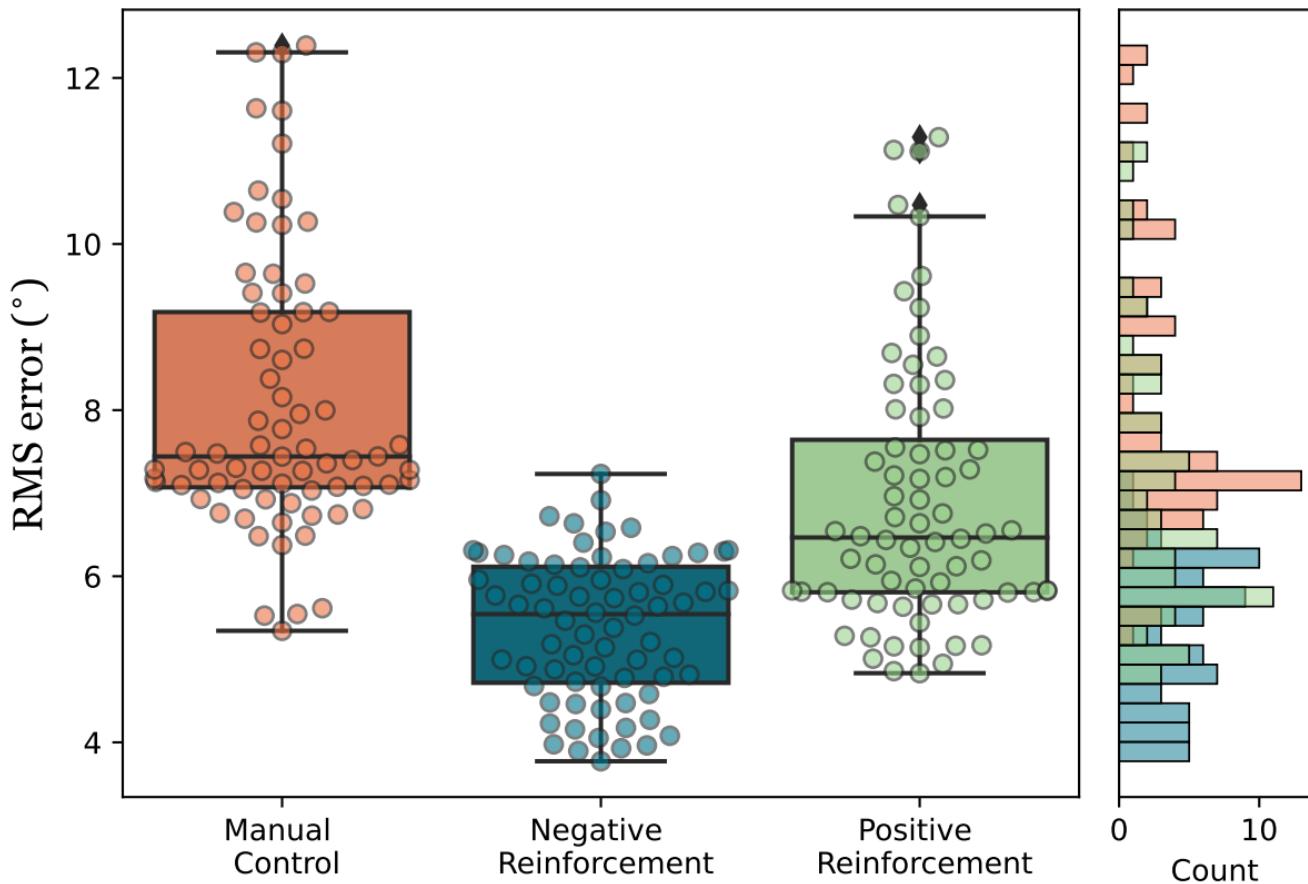
Distribution



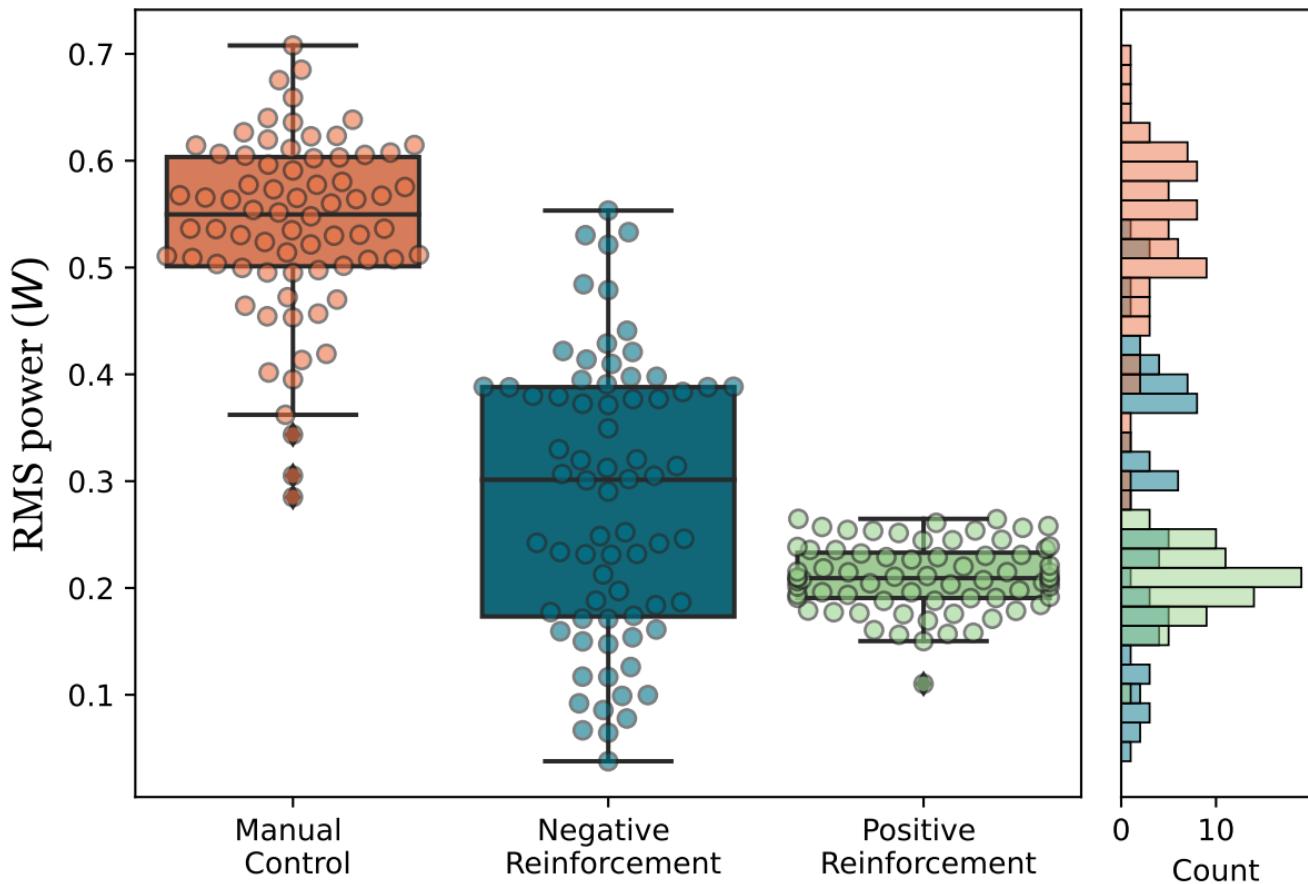
# Objective control Share



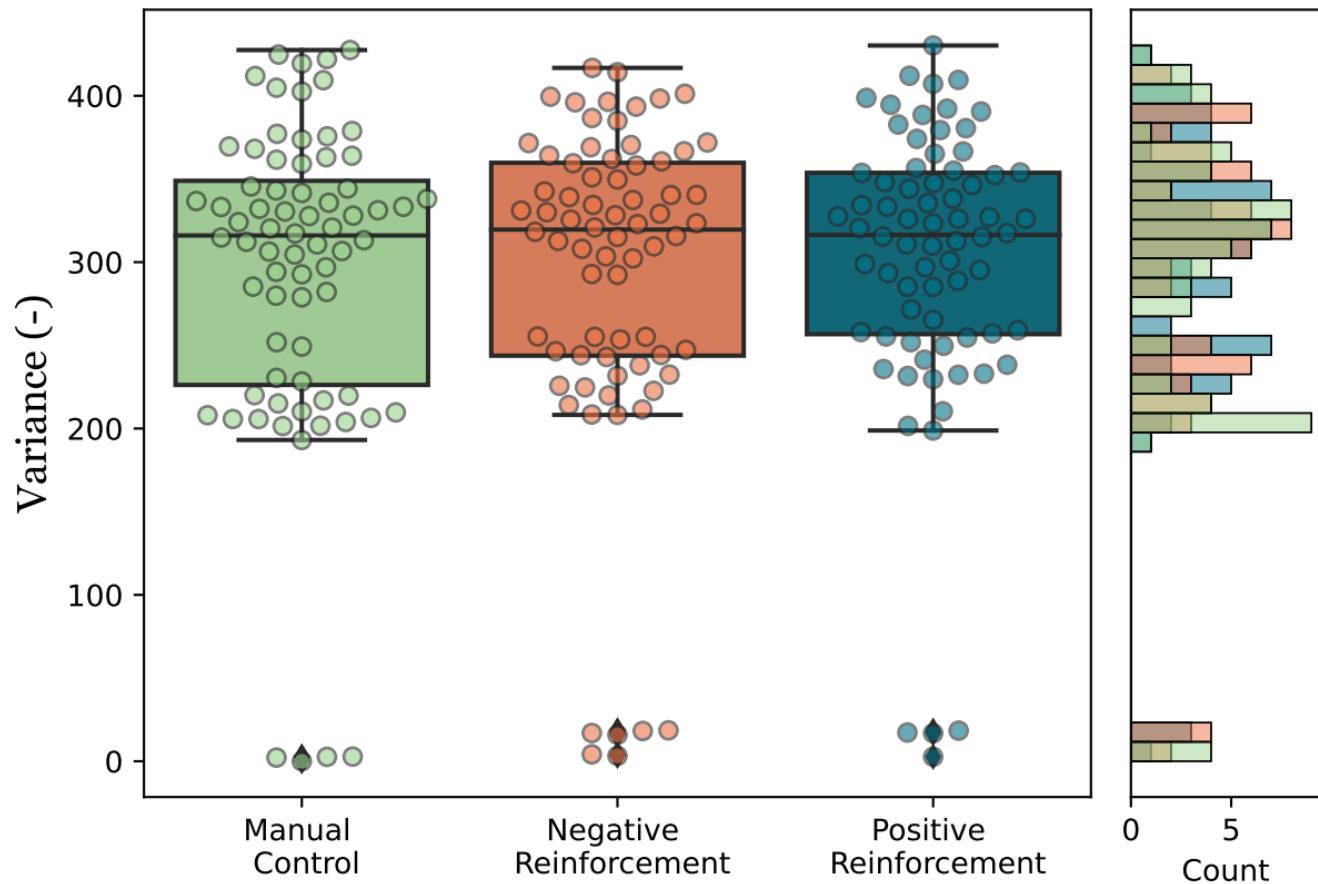
# Steering Angle Error



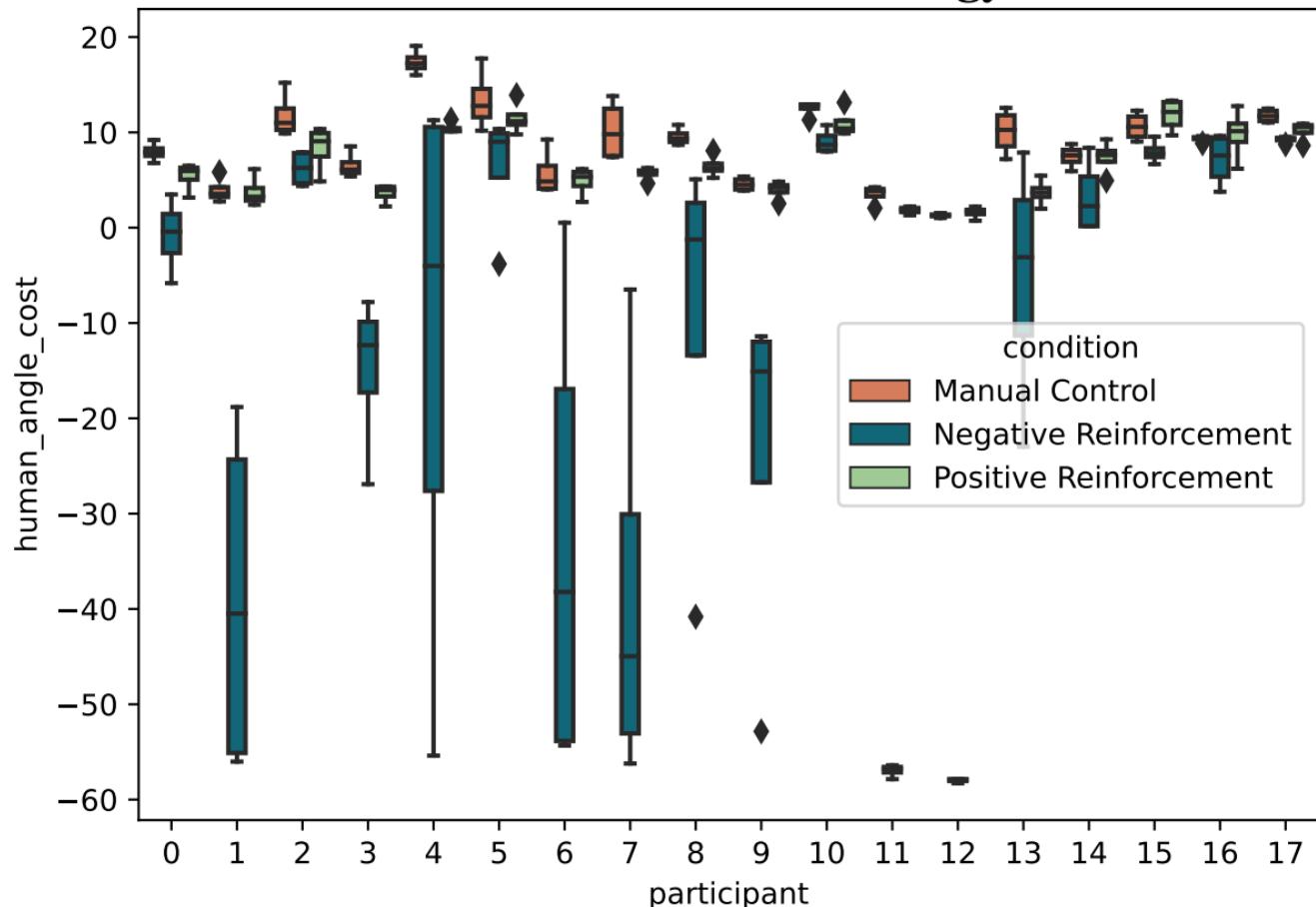
# Human Input Power



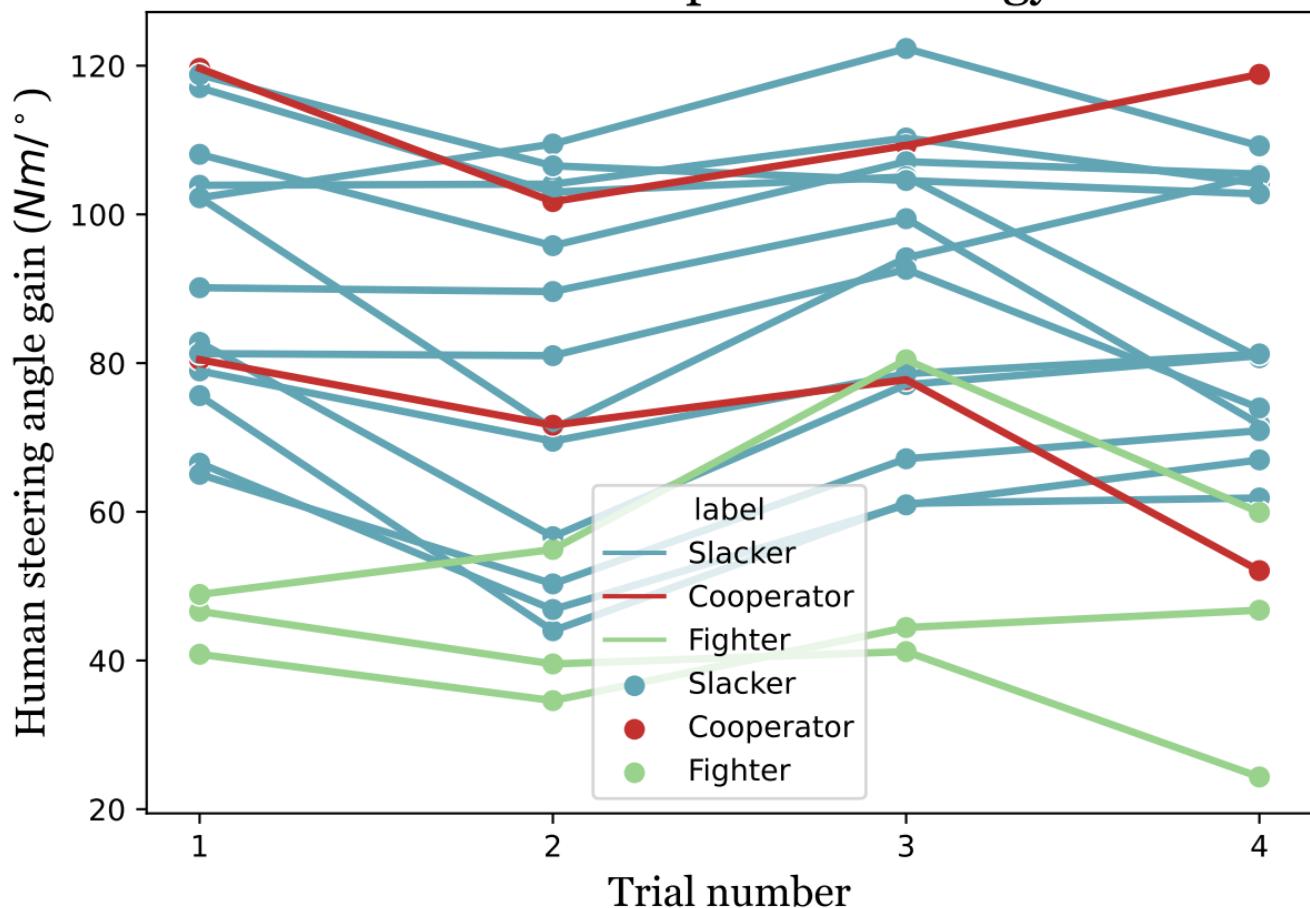
# Cost function variability



# Human control strategy

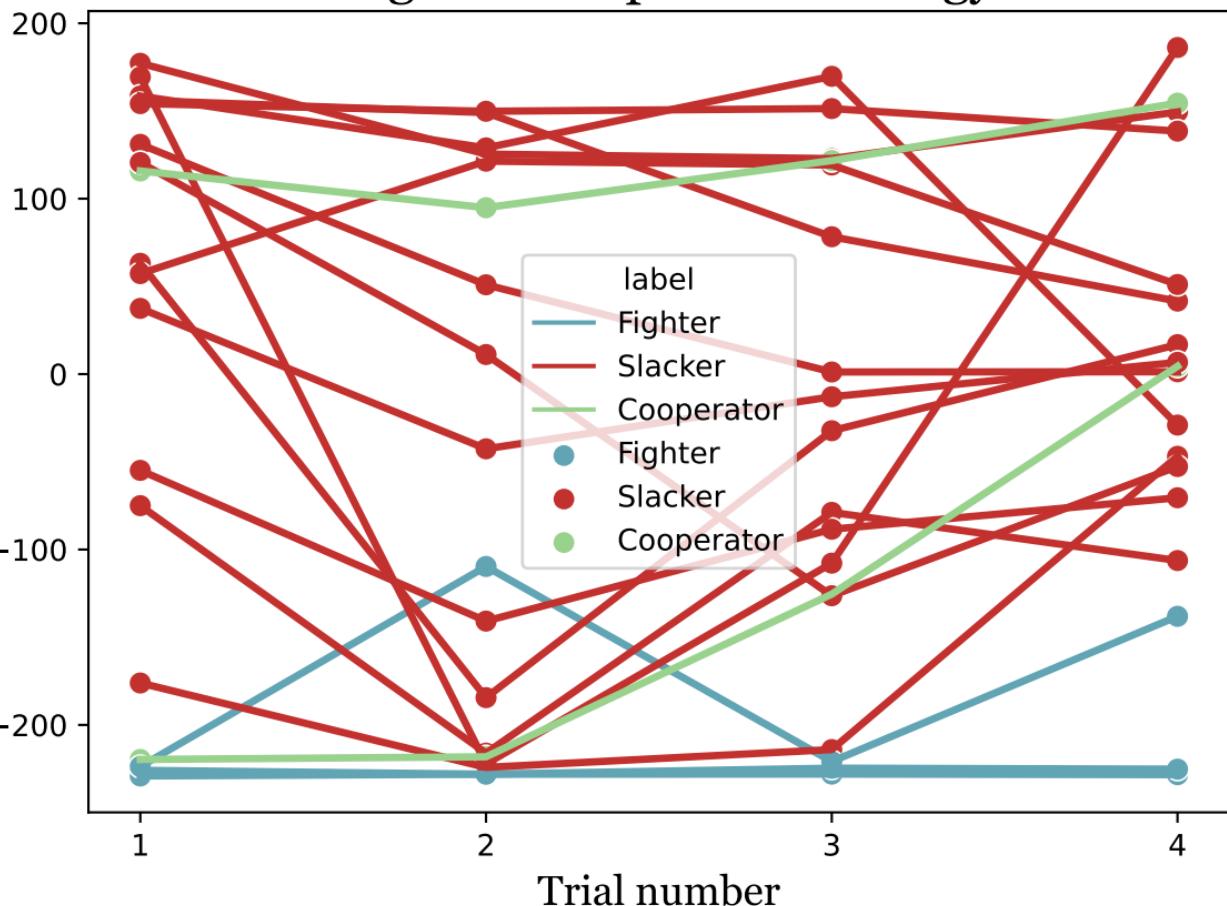


# Positive adaptation strategy

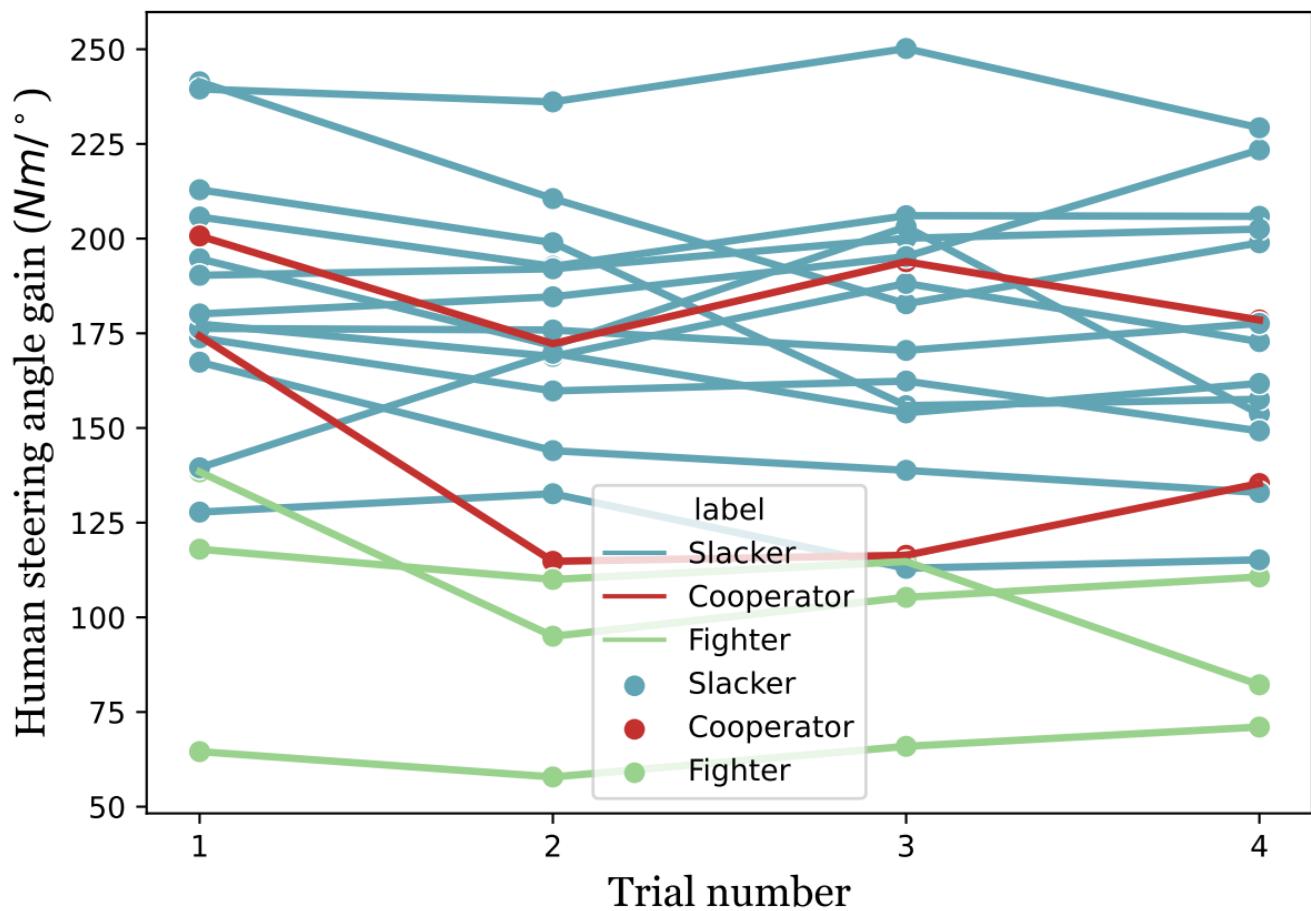


# Negative adaptation strategy

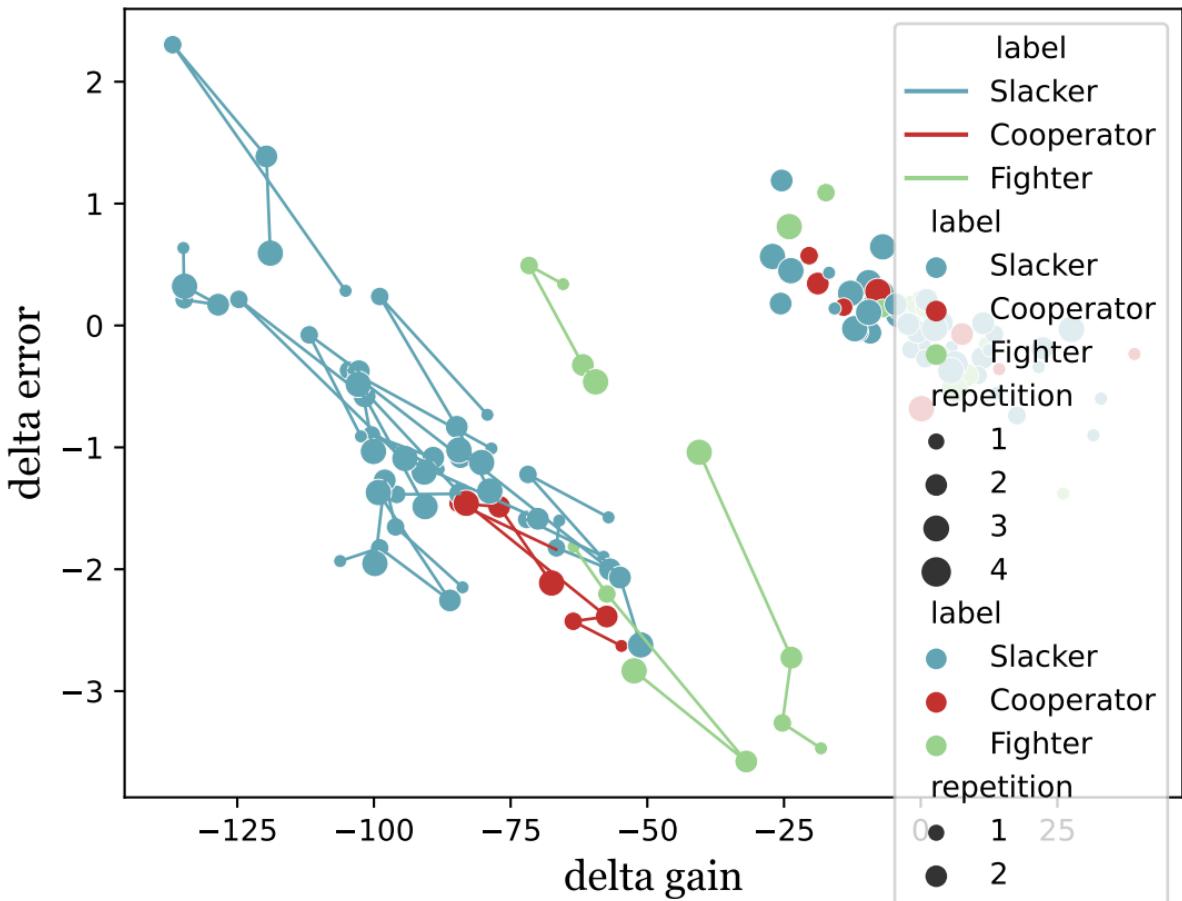
Human steering angle gain ( $Nm/\text{ }^\circ$ )



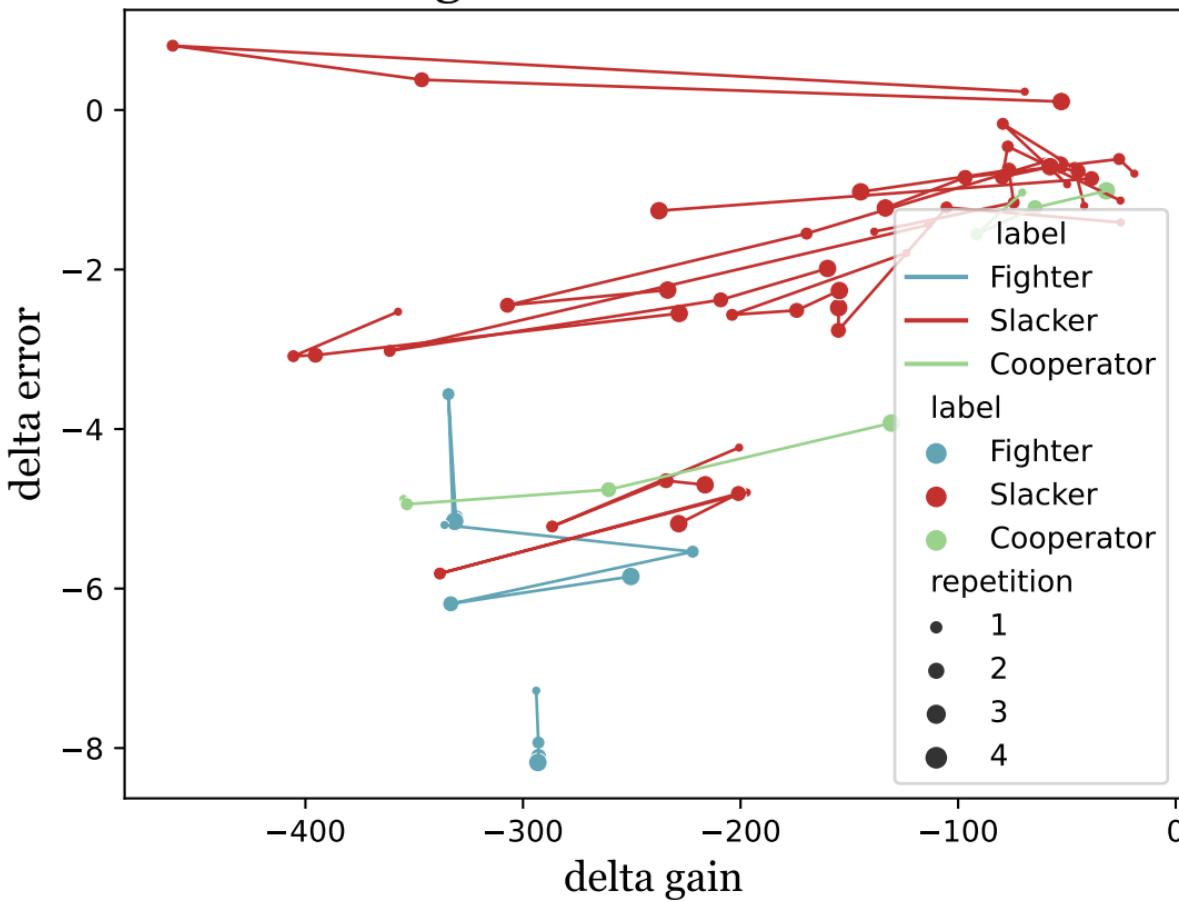
# Manual control



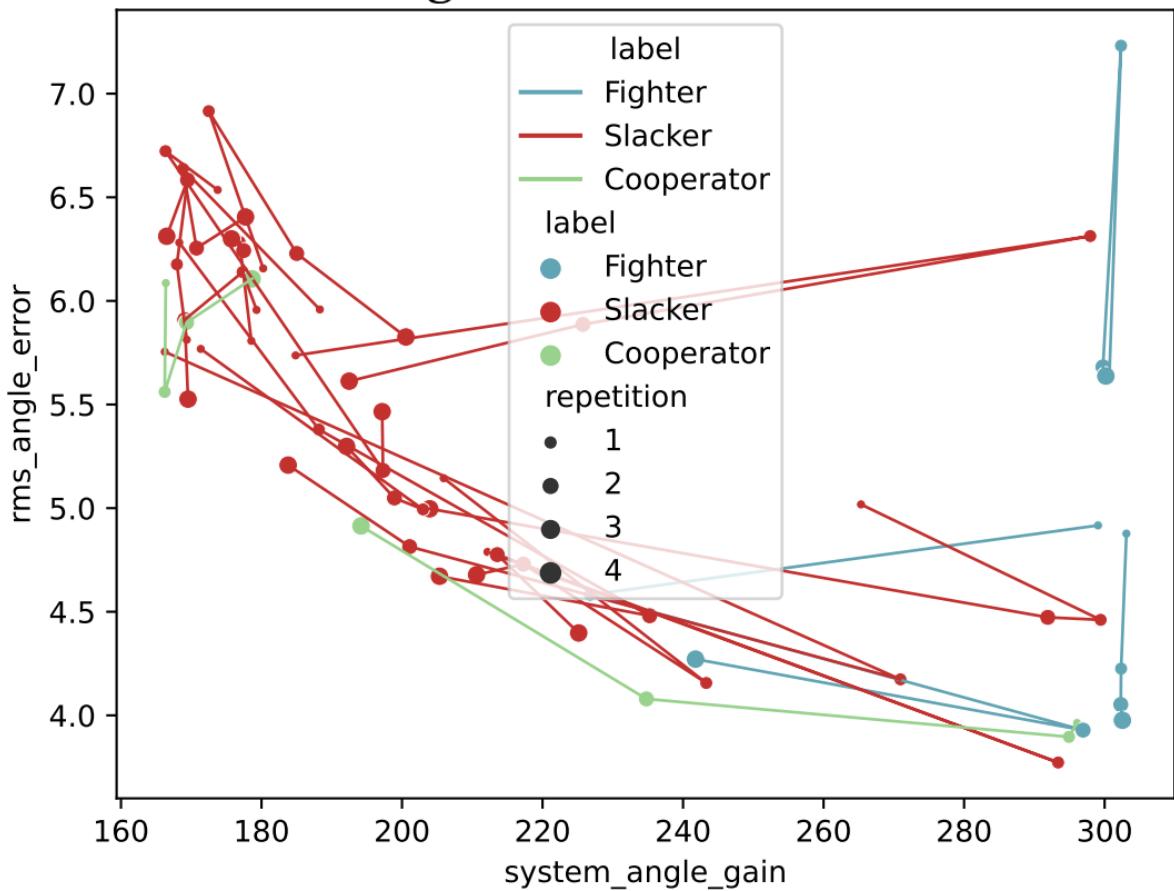
# Positive reinforcement



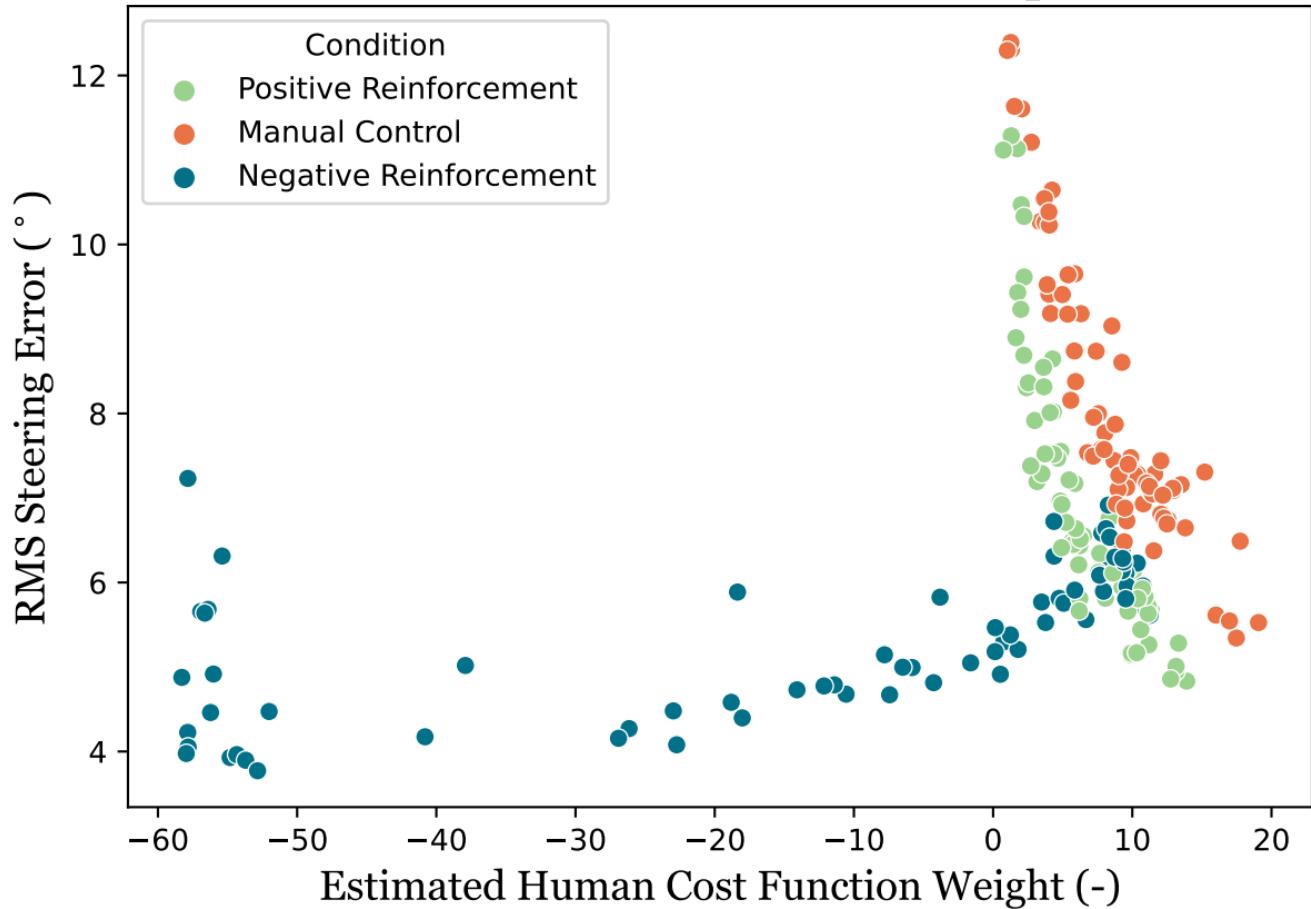
# Negative Reinforcement



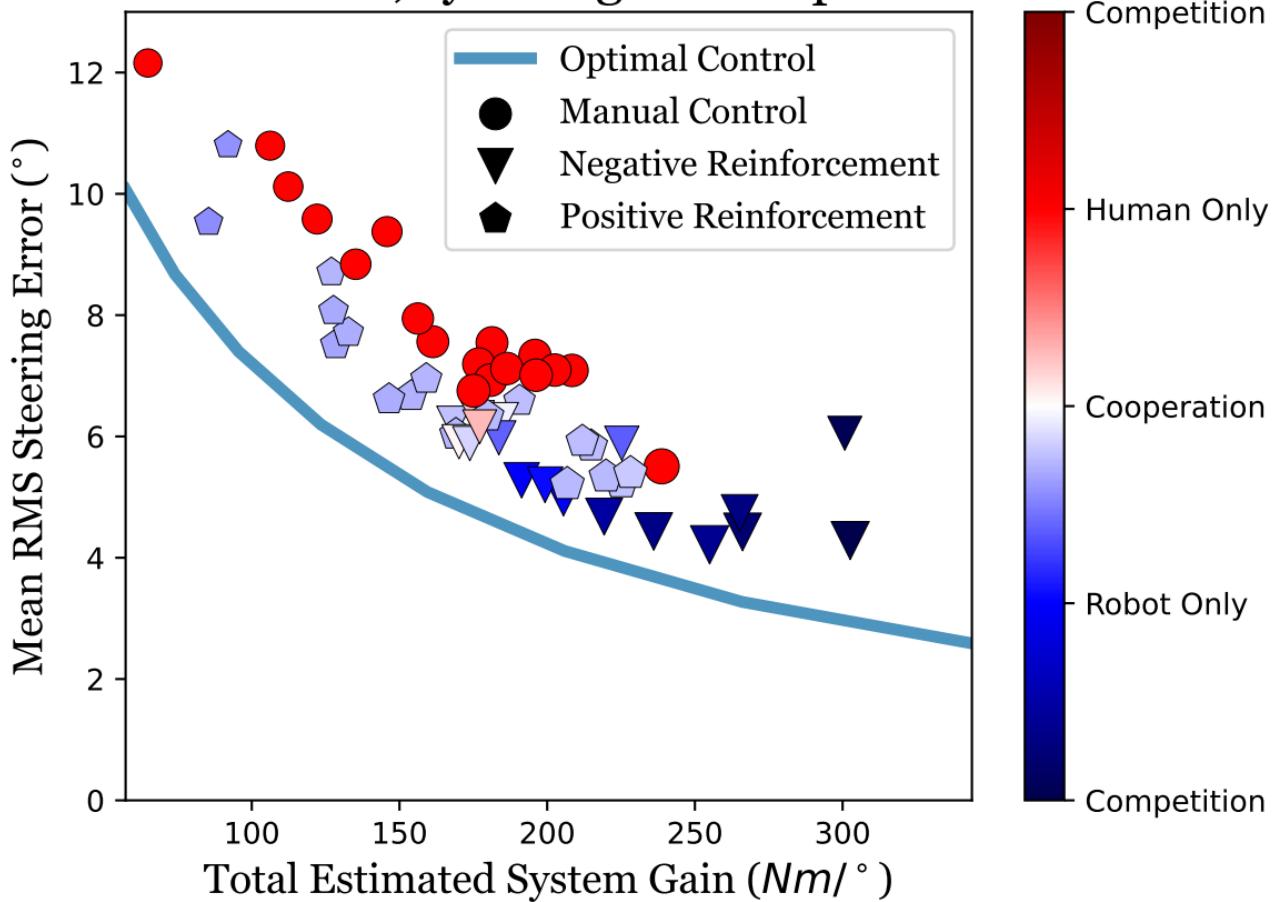
# Negative Reinforcement



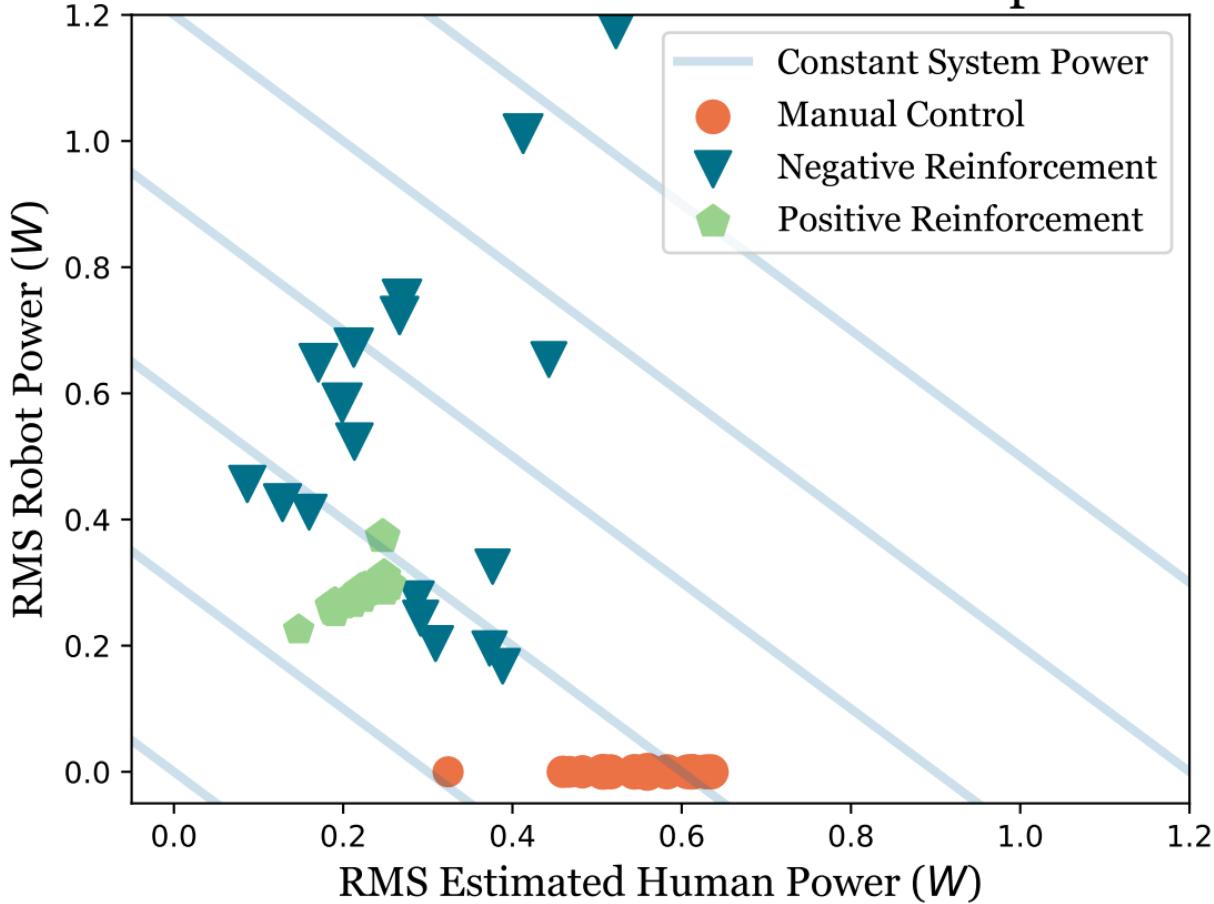
# Effect of human cost function on team performance



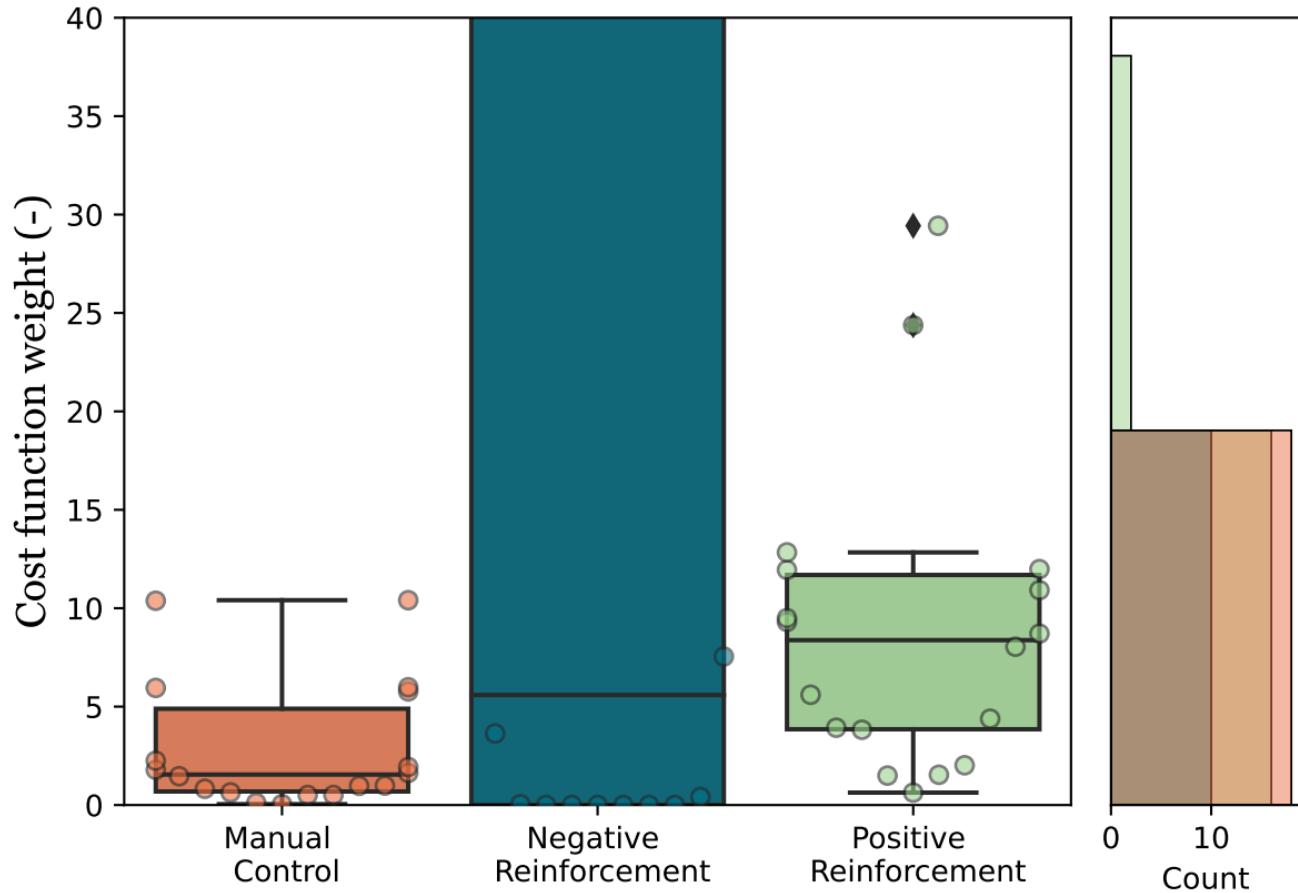
# Interaction mode, system gain and performance



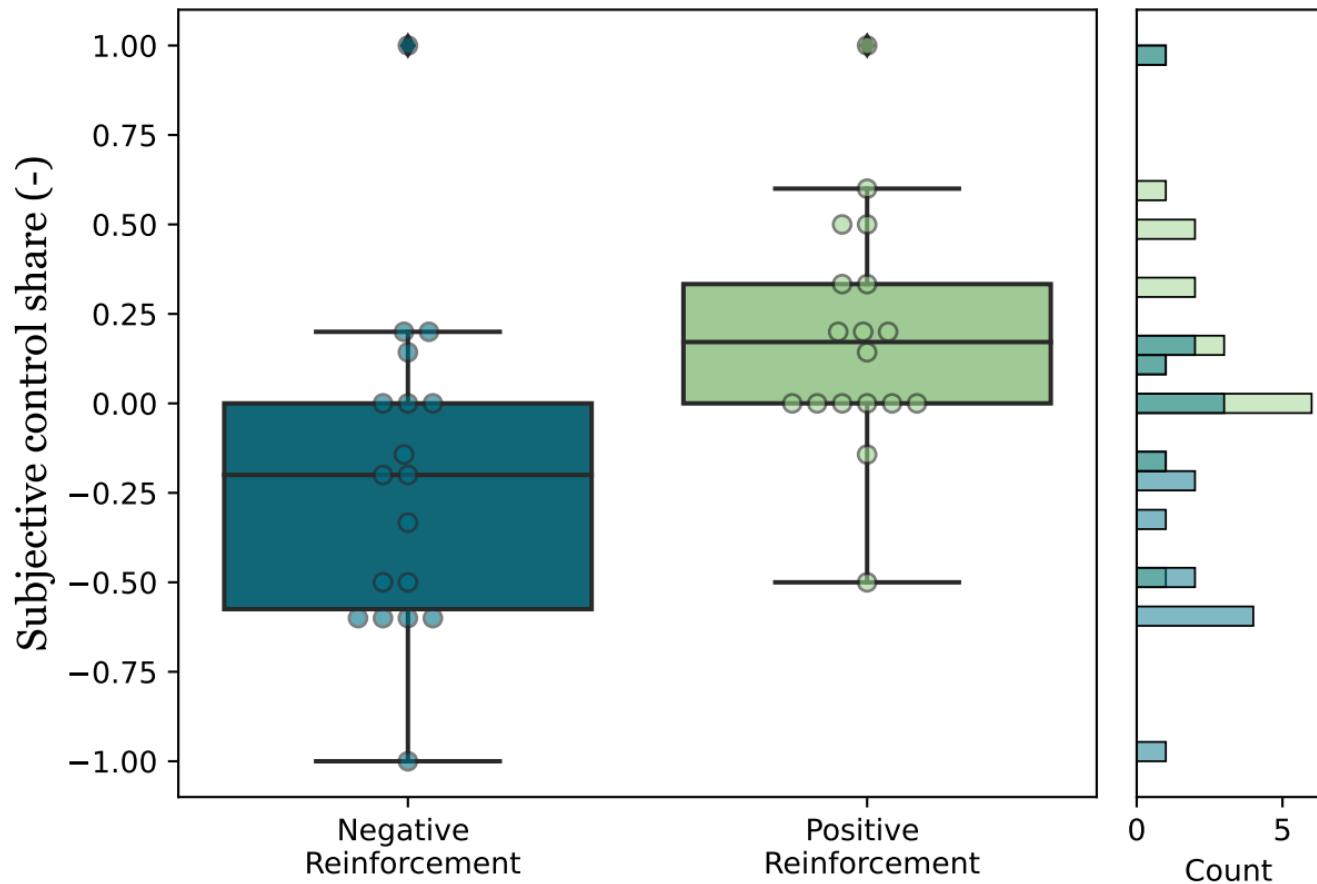
# Relation between human and robot power



## Trial-by-trial variability



# Subjective control share



# Subjective and objective control share

