Handover trajectory in shared frame, n = 6, Robot: Taker
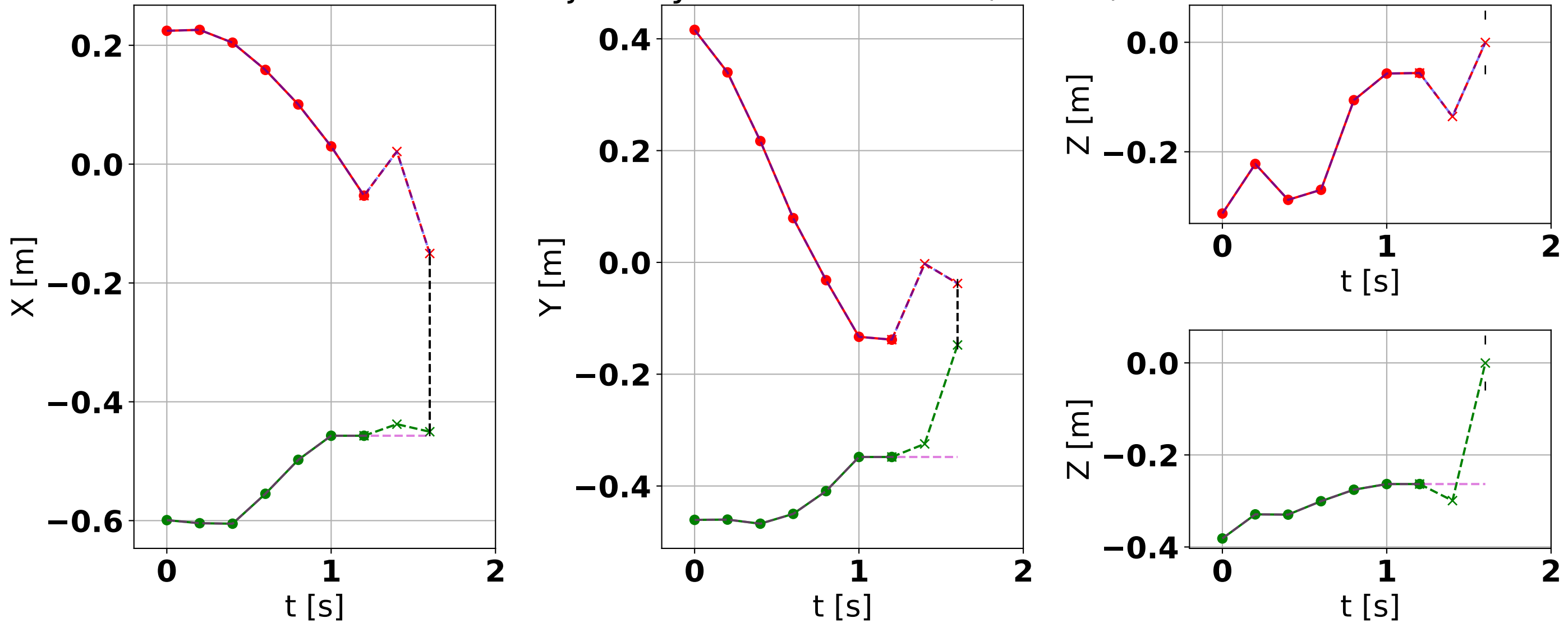
Human position ·—·
Human plan ·—×—·
Robot position ·—●—·
Robot plan ·—×—·
True human position ·– –·
True robot position ·– –·
Predicted handover, K8 = 0.01 ·–+–·