Handover trajectory in shared frame, n = 3, Robot: Taker

- Human position (green, solid, circle markers)
- Human plan (green, dashed, x markers)
- Robot position (red, solid, circle markers)
- Robot plan (red, dashed, x markers)
- True human position (magenta, dashed)
- True robot position (blue, dashed)
- Predicted handover, K7 = 0.01 (black, dashed)