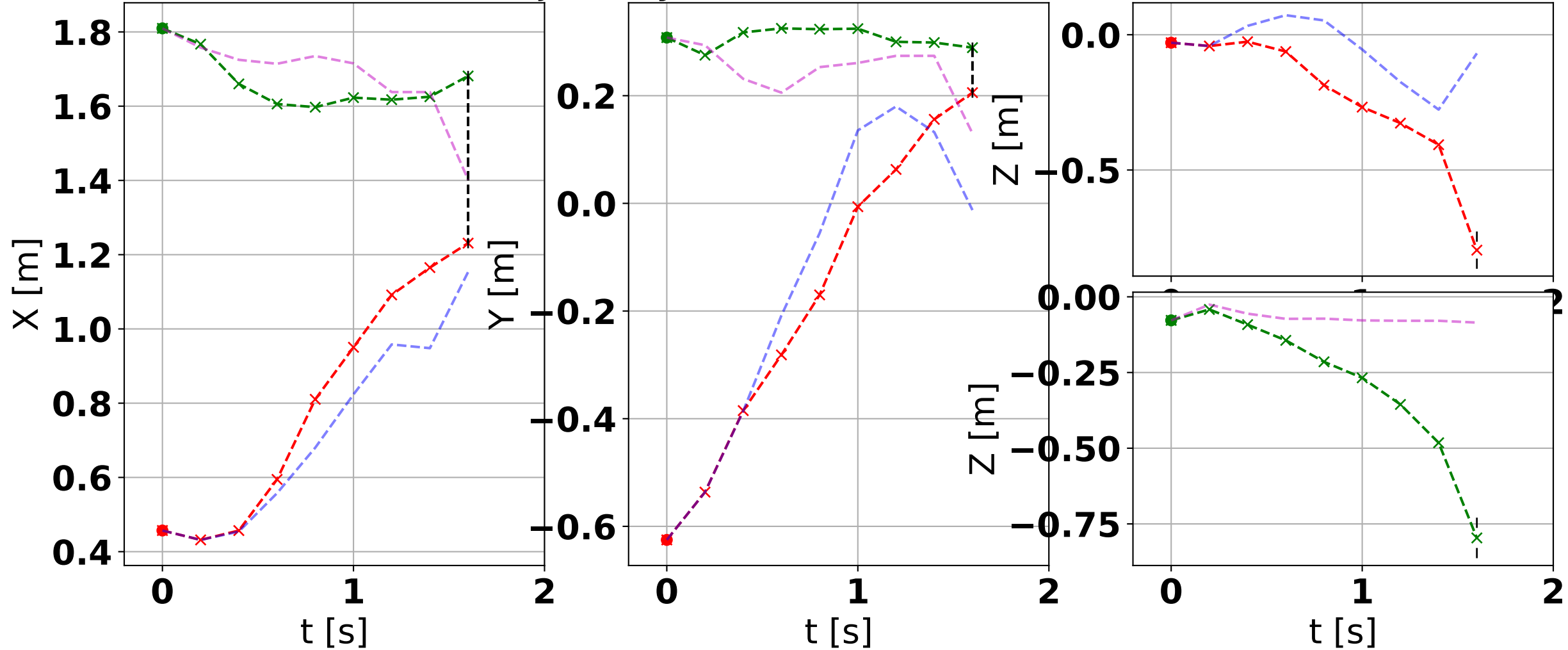


Handover trajectory in world frame, $n = 0$, Robot: Taker



- | | | | |
|--|---|--|----------------------------|
| | Human position | | True human position |
| | Human plan | | True robot position |
| | Robot position | | Robot plan |
| | Predicted handover, $K8 = 0.01$ | | |