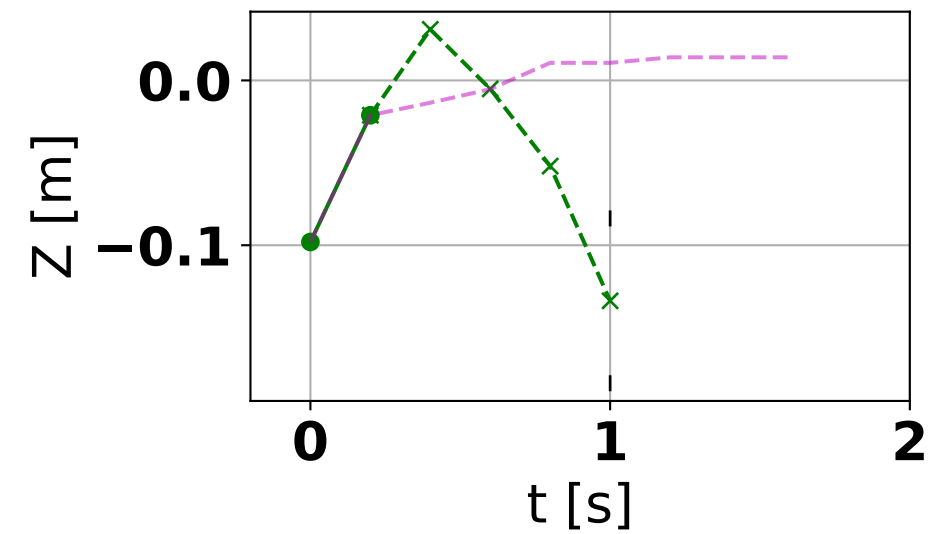
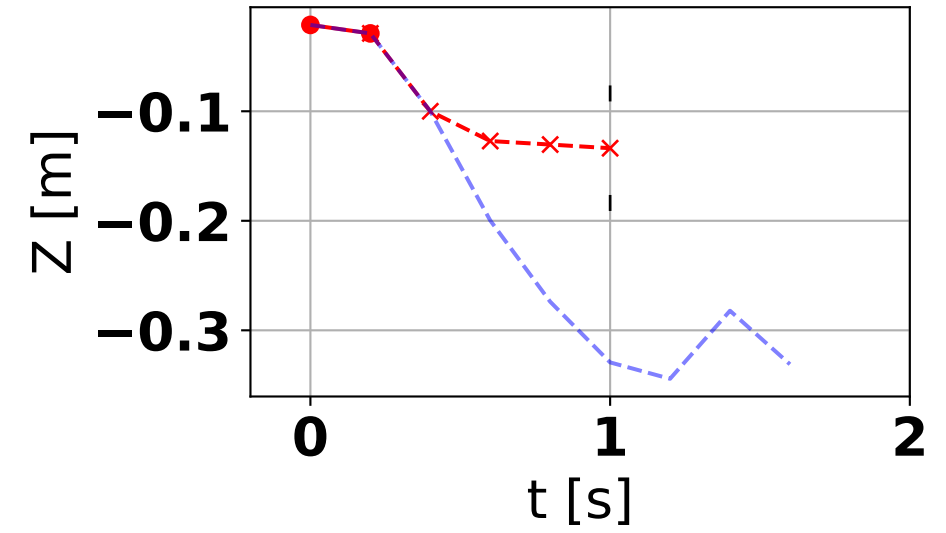
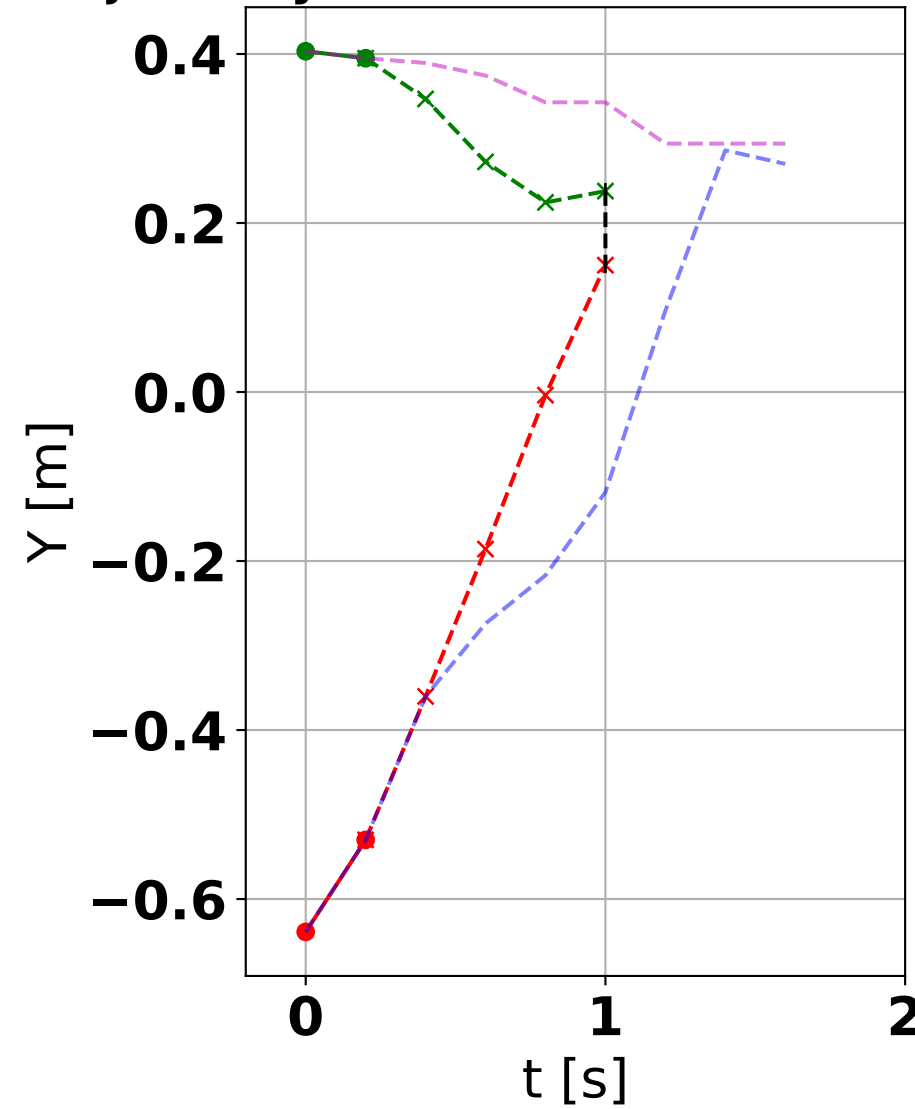
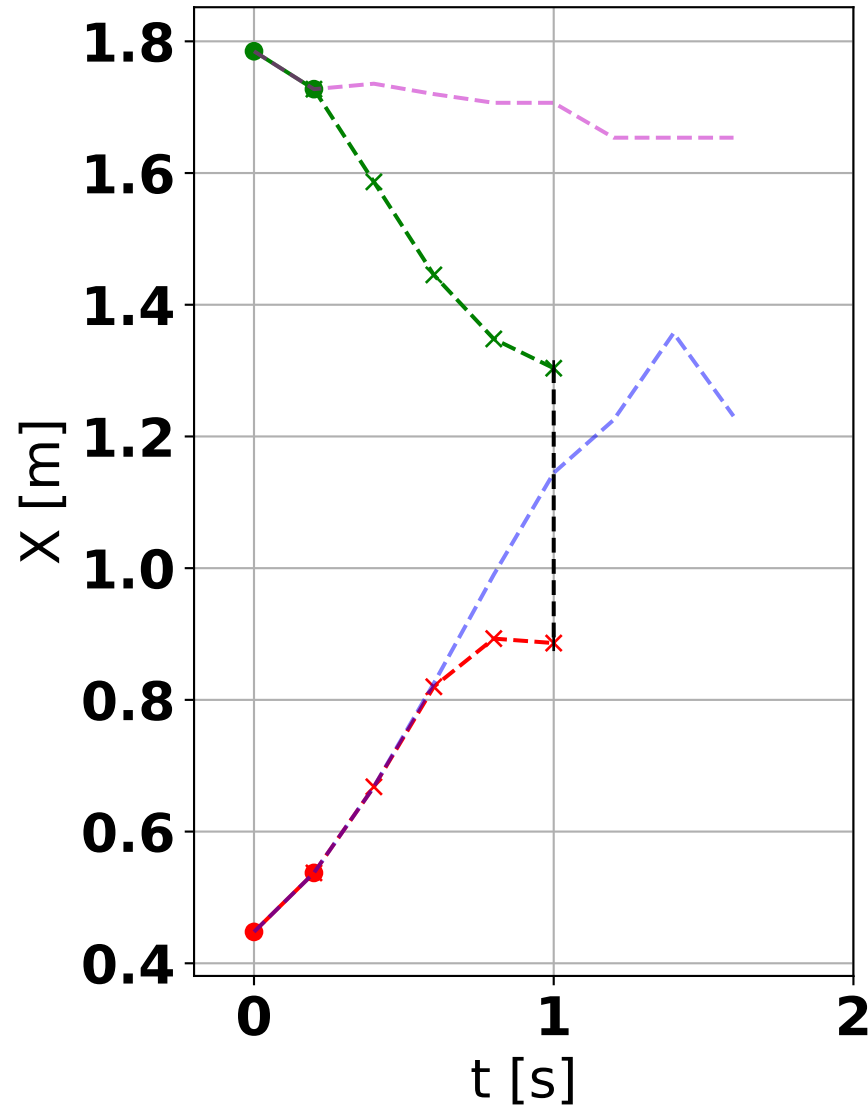


Handover trajectory in world frame, $n = 1$, Robot: Taker



- | | | | |
|--|-----------------------|--|---|
| | Human position | | True human position |
| | Human plan | | True robot position |
| | Robot position | | Predicted handover, $K5 = 0.01$ |
| | Robot plan | | |