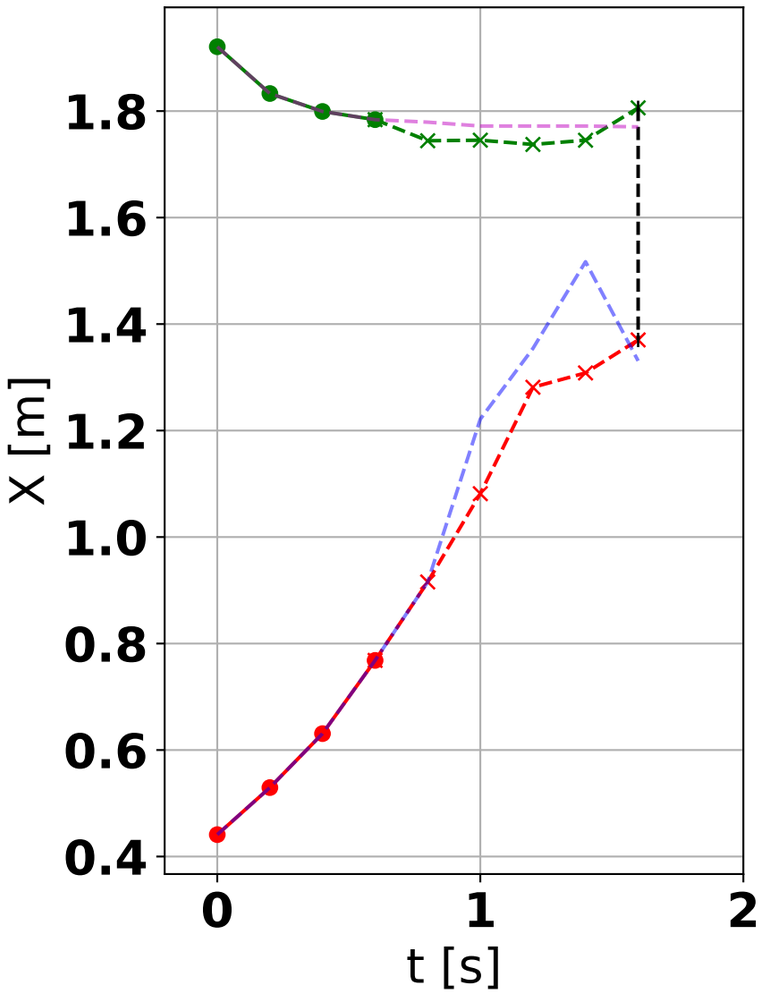
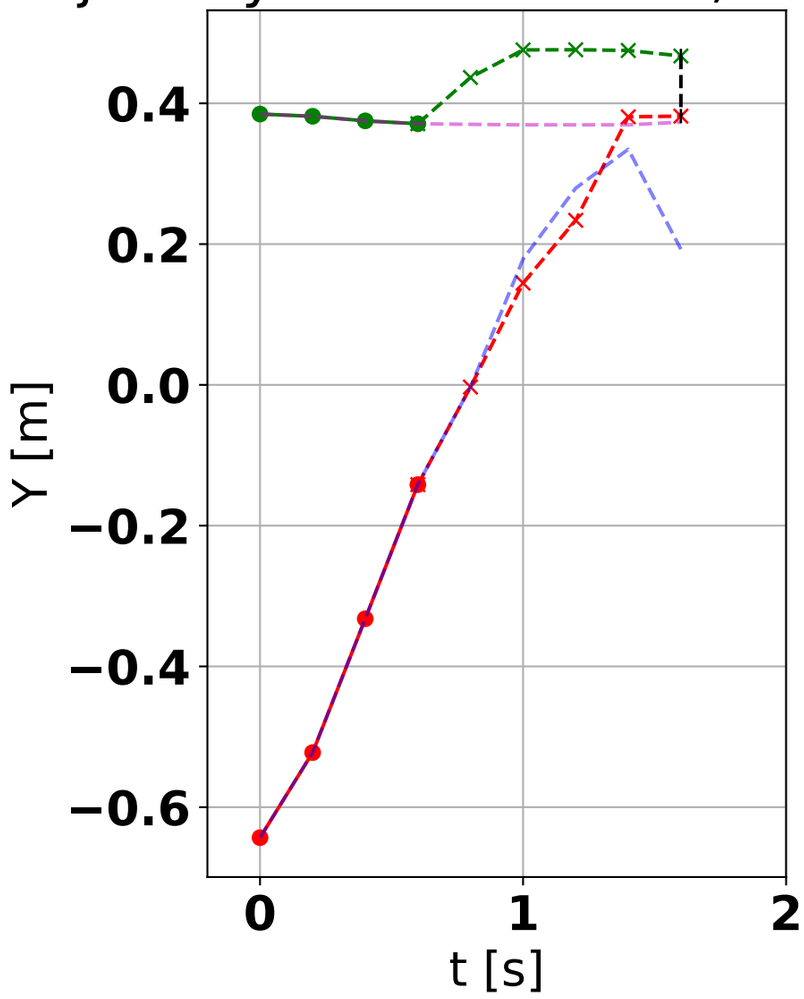
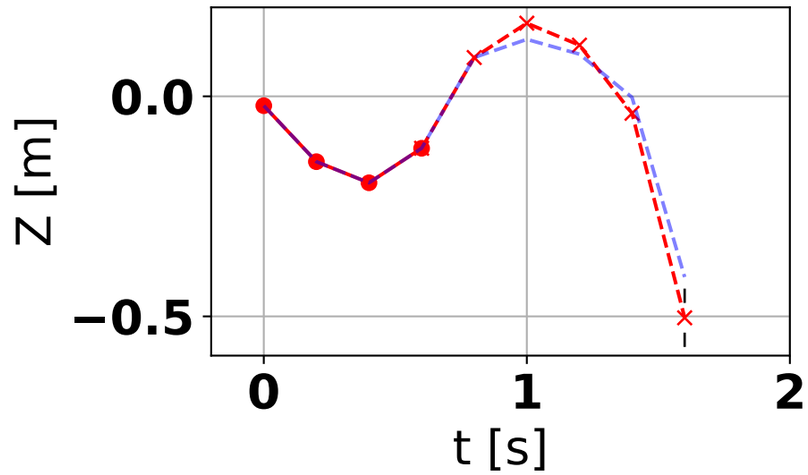
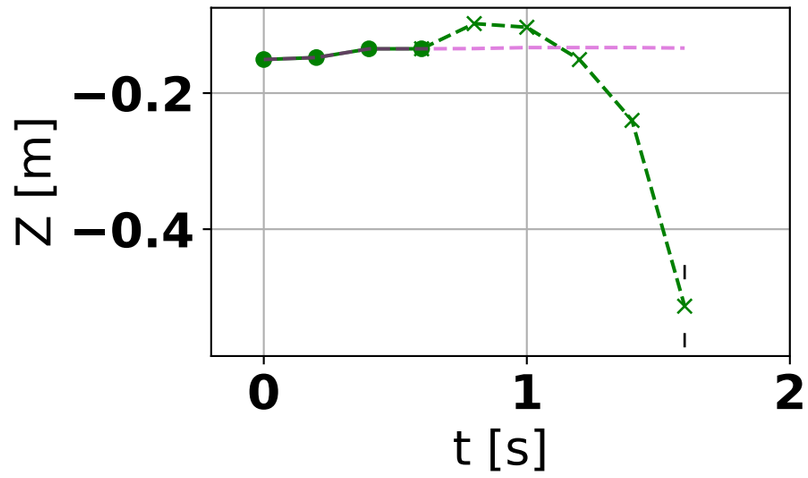
Handover trajectory in world frame, n = 3, Robot: Taker









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