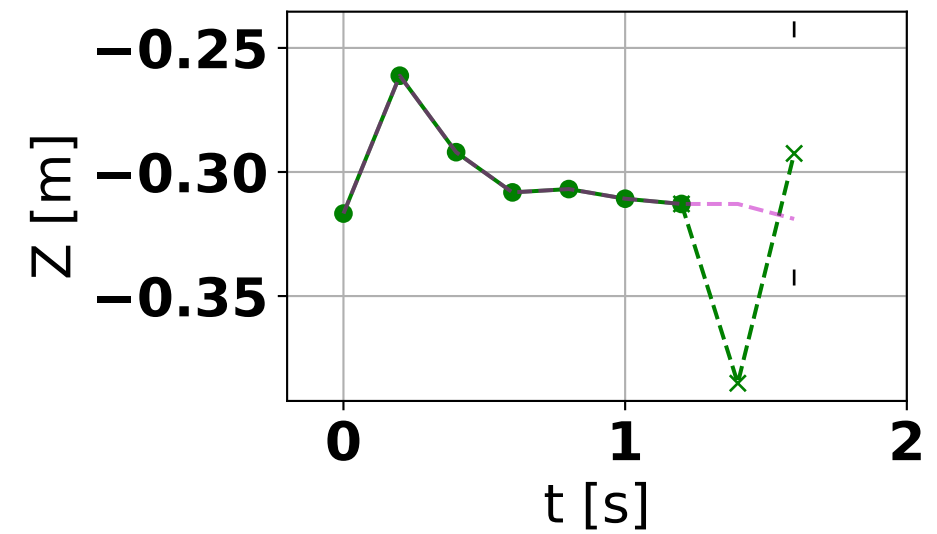
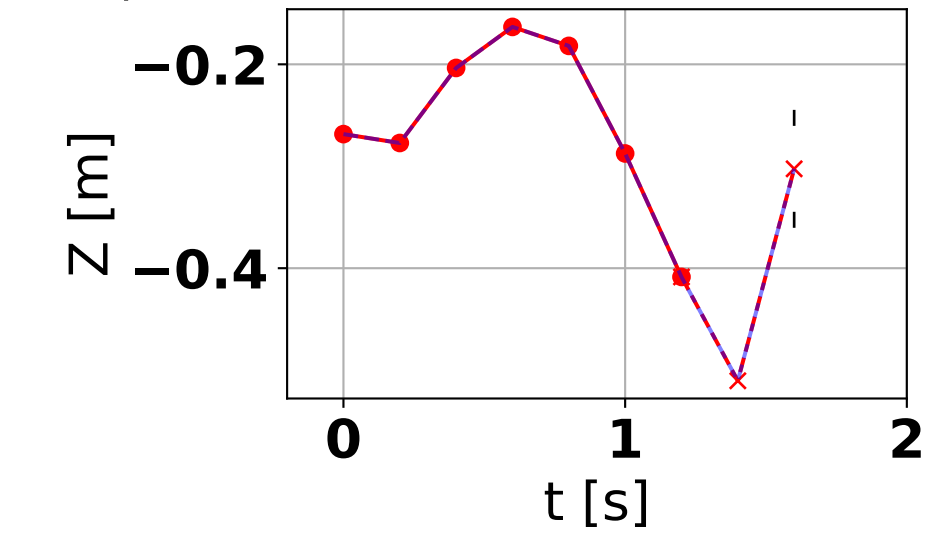
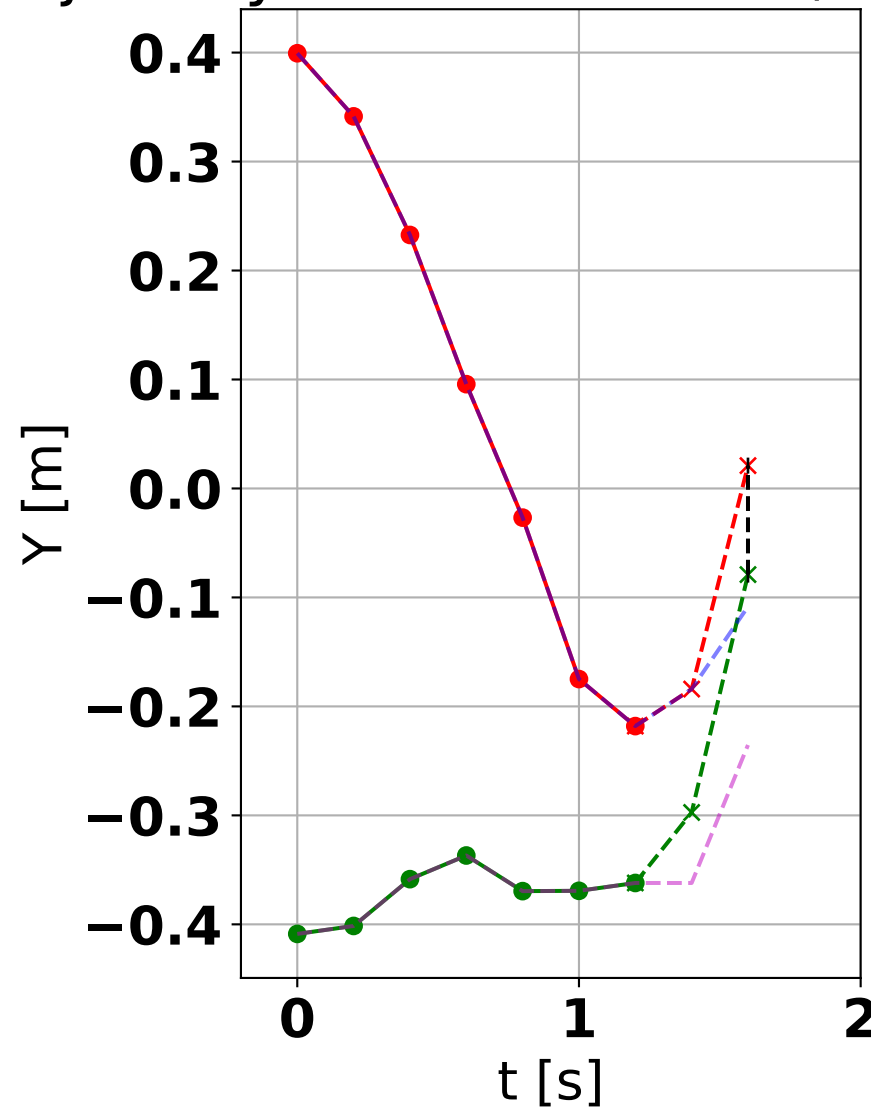
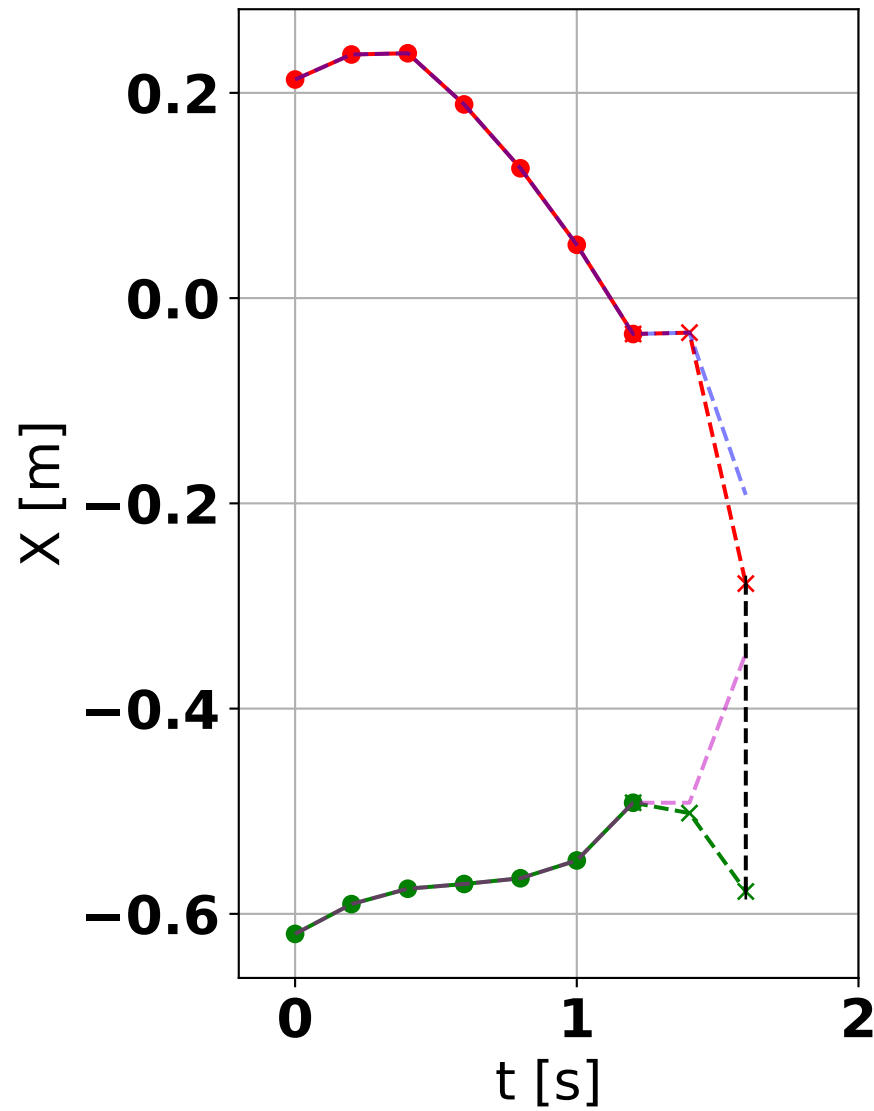


Handover trajectory in shared frame, $n = 6$, Robot: Taker



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