Handover trajectory in world 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, K8 = 0.01 (black, dashed)