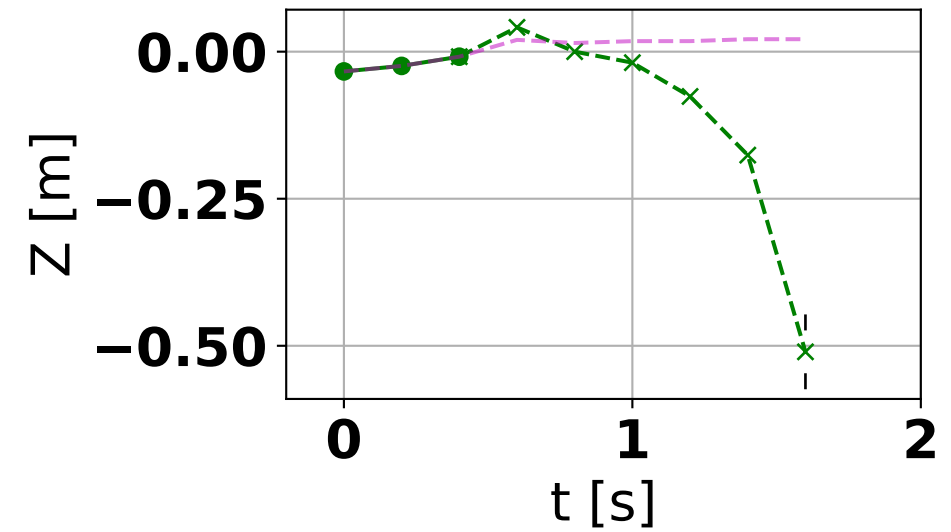
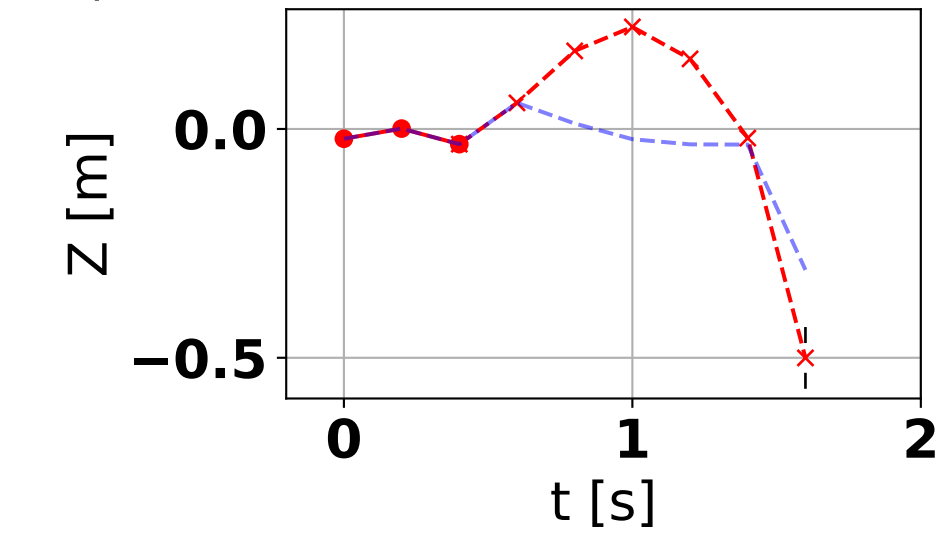
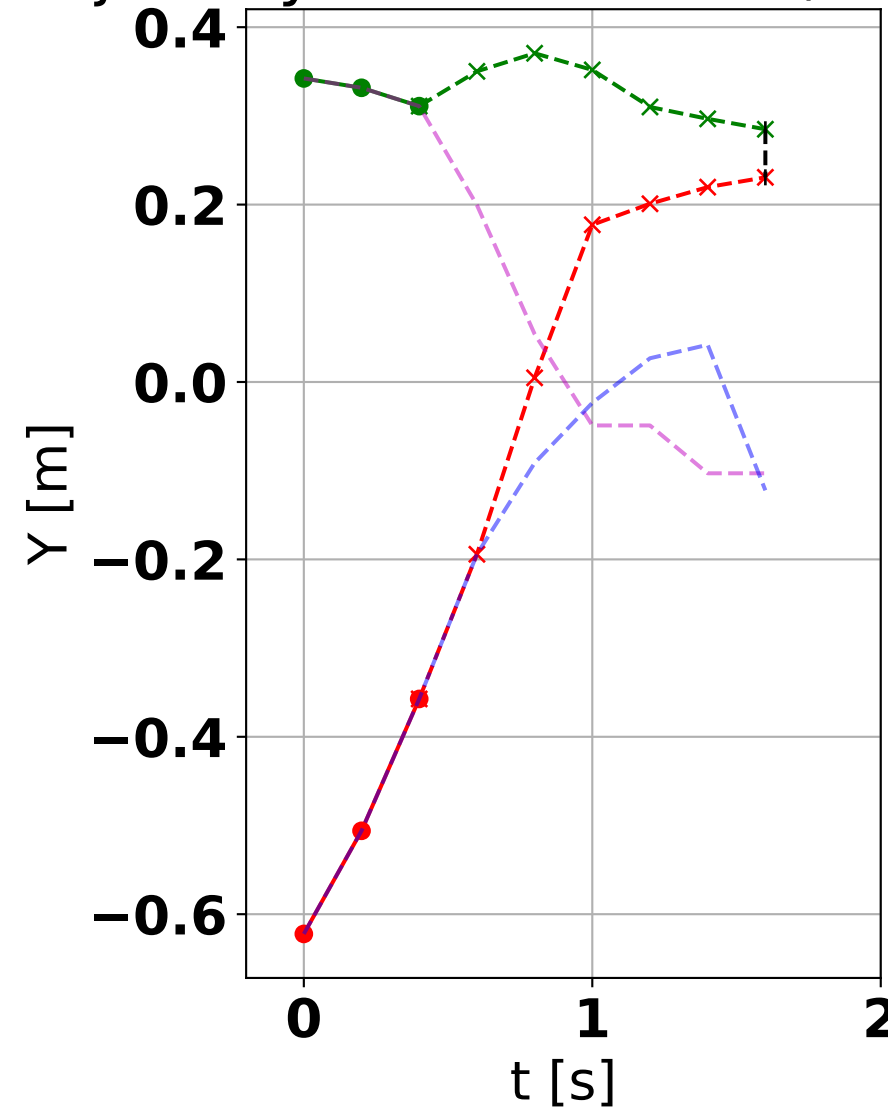
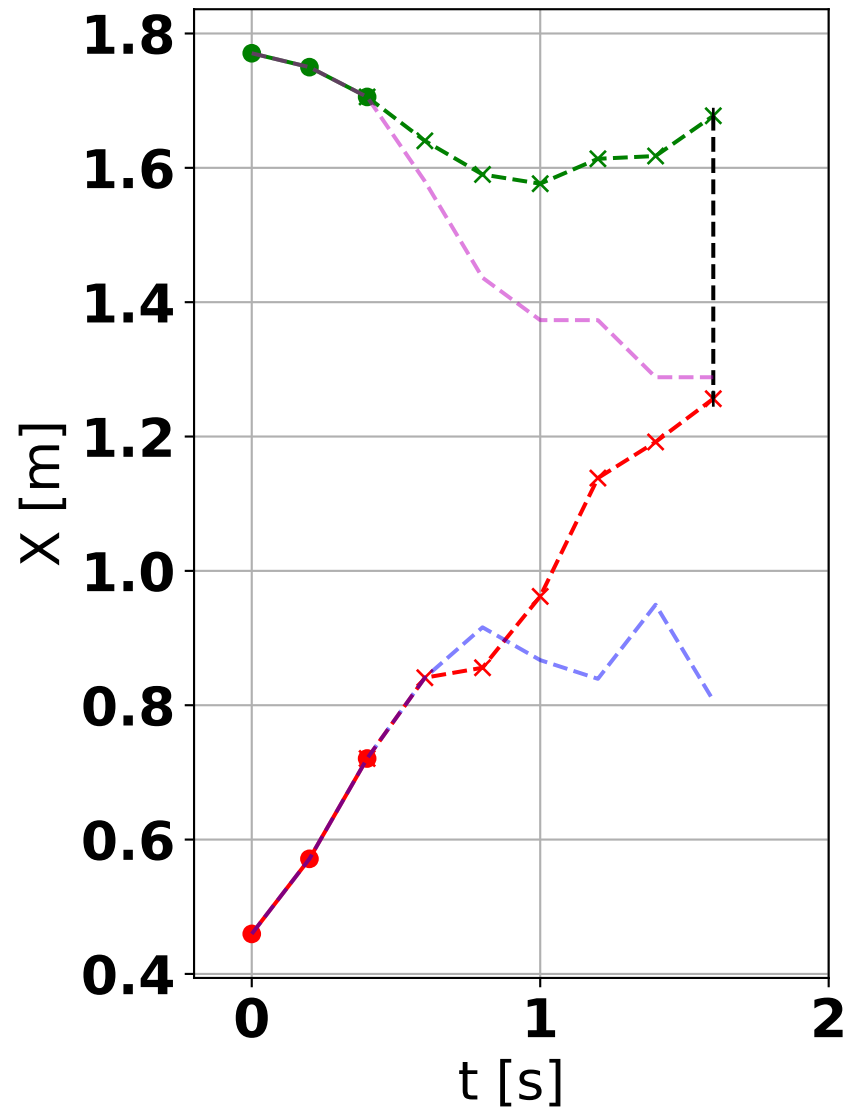


Handover trajectory in world frame, n = 2, Robot: Taker



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