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

- **Human position** (solid green with dots)
- **Human plan** (dashed green with x)
- **Robot position** (solid red with dots)
- **Robot plan** (dashed red with x)
- **True human position** (dashed pink)
- **True robot position** (dashed blue)
- **Predicted handover, K7 = 0.06** (dashed black with +)