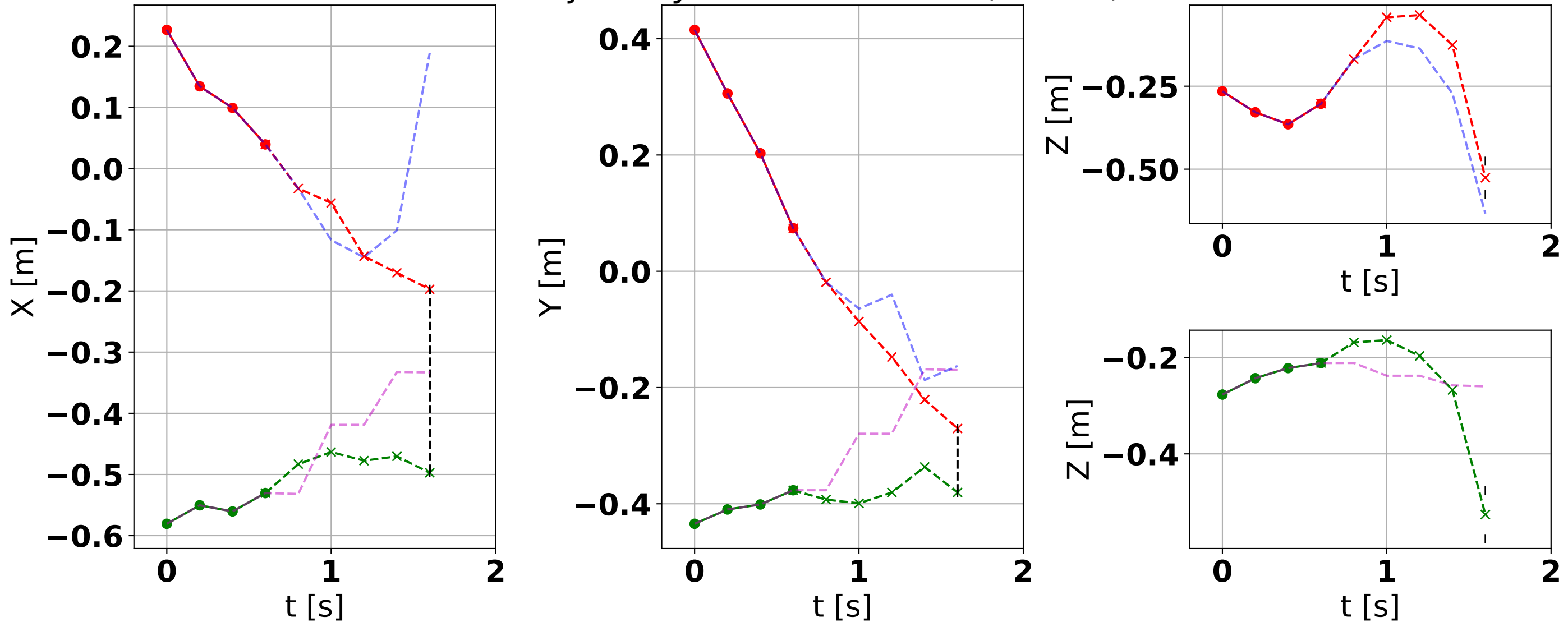Handover trajectory in shared frame, n = 3, Robot: Taker