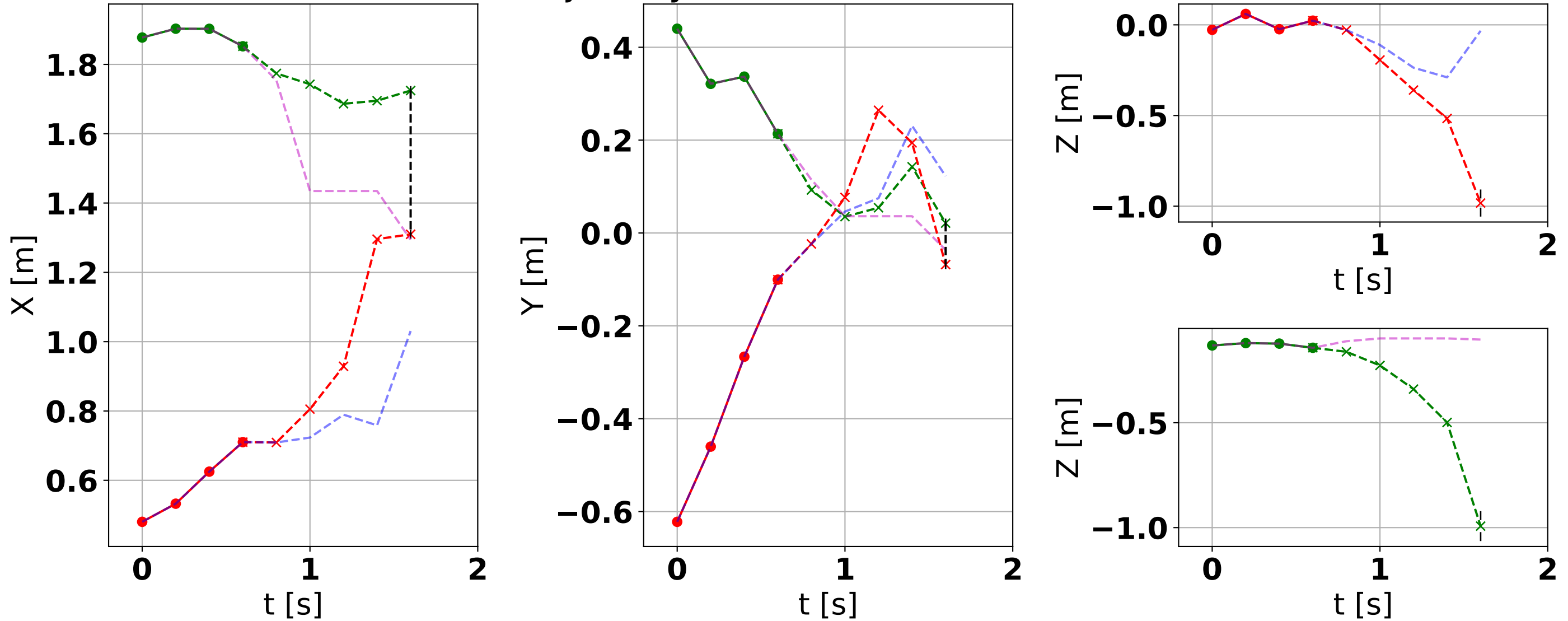


Handover trajectory in world frame, $n = 3$, Robot: Taker



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