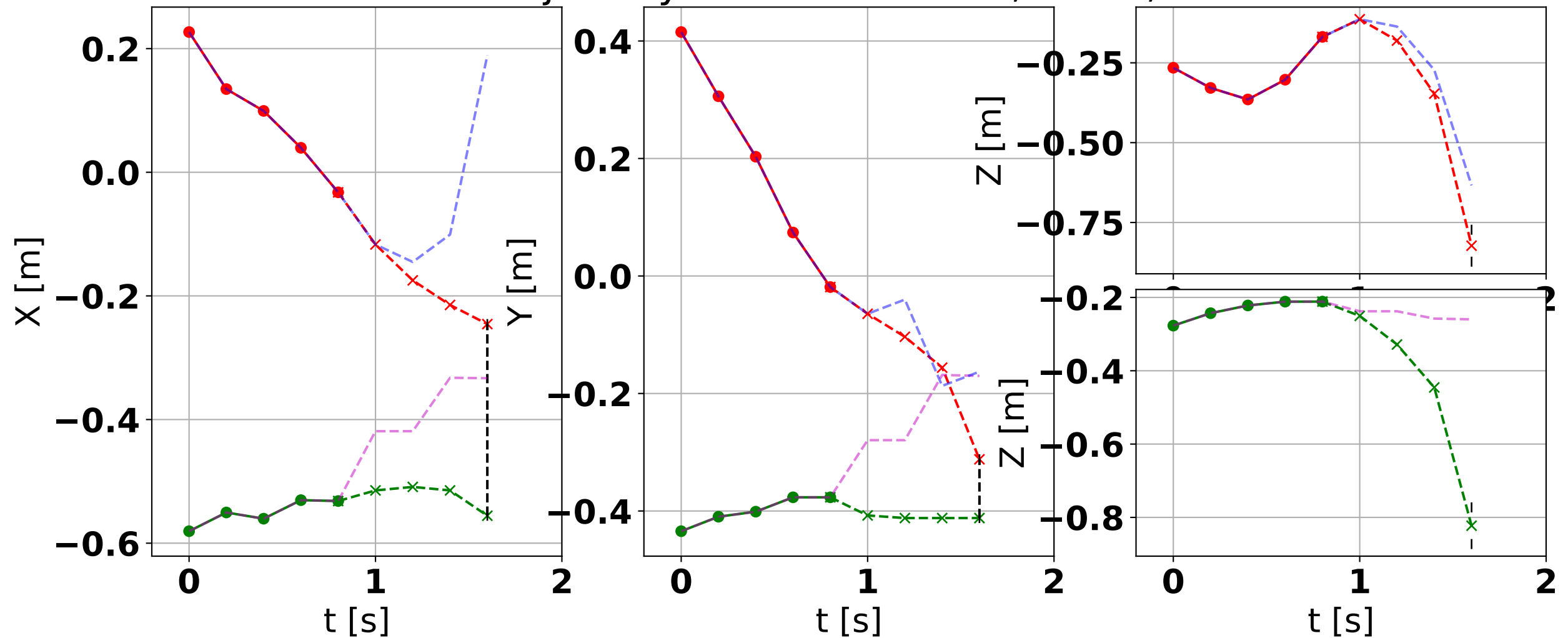


Handover trajectory in shared frame, $n = 4$, Robot: Taker



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