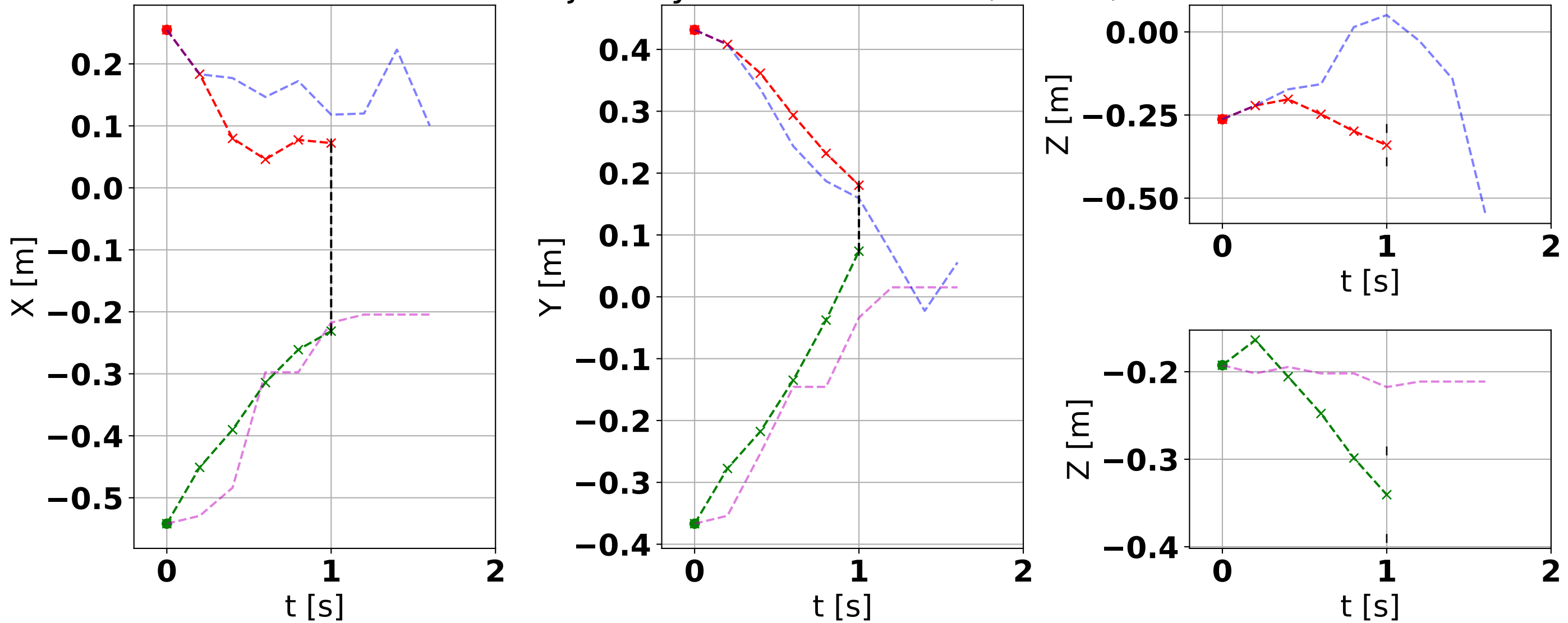Handover trajectory in shared frame, n = 0, Robot: Taker