Handover trajectory in world frame, n = 0, Robot: Taker
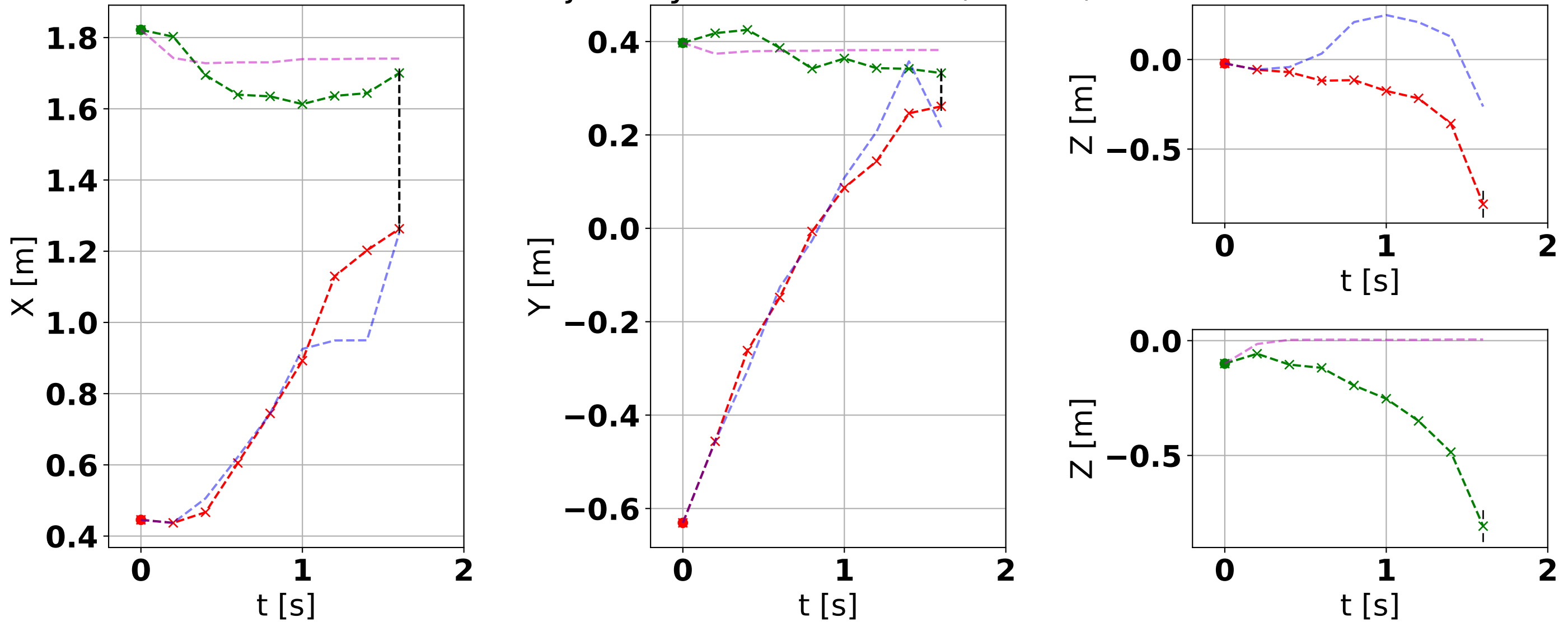
Legend:
- **Human position**
- **Human plan**
- **Robot position**
- **Robot plan**
- **True human position**
- **True robot position**
- **Predicted handover, K8 = 0.00**