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

- **Human position** (green solid with dots)
- **Human plan** (green dashed with x)
- **Robot position** (red solid with dots)
- **Robot plan** (red dashed with x)
- **True human position** (pink dashed)
- **True robot position** (blue dashed)
- **Predicted handover, K7 = 0.01** (black dashed)