Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 -0.5Z [m] 0.2 0.0 -1.0E -0.2 × Y [m] 0.0 t [s] -0.4-0.2-0.5Z [m]-0.6-0.4-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**