Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 [ **-0.5** 0.3 0.1 0.2 0.0 -1.00.1 -0.1E −0.1 × −0.2 t [s] 0.0 -0.1**-0.3** -0.5-0.2Z [m]-0.4-0.3-0.5-0.4-1.0-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.00 **Robot plan**