Handover trajectory in shared frame, n = 3, Robot: Taker 0.2 0.4 -0.5[m] -1.00.0 0.2 **-1.5** -0.2 X [m]Y[m]0.0 t [s] -0.4-0.5-0.2 = -1.0 -0.6-0.4-1.5 0 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**