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