Handover trajectory in shared frame, n = 2, Robot: Taker -0.40.4 0.2 [E] **-0.6** 0.3 0.2 0.0 -0.80.1 Y [m] t [s] 0.0 -0.1-0.4-0.4-0.2 Z[m]-0.6 -0.3-0.6-0.8-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** Predicted handover, K7 = 0.01**Robot plan**