Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 [E -0.5 N 0.1 0.2 0.0 -1.0E -0.1 × -0.2 Y [m] 0.0 t [s] **-0.3** -0.2-0.5Z [m]-0.4-0.5 -0.4-1.0-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position** ----- Predicted handover, K8 = 0.01 **Robot position Robot plan**