Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 0.2 -0.4Z [m] 0.2 0.0 -0.6E -0.2 × Y[m]0.0 t [s] **-0.3** -0.4-0.2 [ −0.4 -0.6-0.5-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.01 **Robot plan**