Handover trajectory in shared frame, n = 5, Robot: Taker 0.2 0.4 0.0 Z[m]0.0 0.2 -0.5Y [m] 0.0 t [s] -0.4-0.2Z [m] 0.0 -0.2**-0.6** -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**