Handover trajectory in shared frame, n = 3, Robot: Taker 0.0 0.4 0.2 Z[m]0.0 0.2 -0.5Y [m] t [s] 0.0 **-0.2** -0.4□ N -0.4 -0.2-0.6-0.4**-0.6** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**