Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 0.2 -0.4Z [m]0.3 0.2 -0.6 0.0 0.1 Y [m] \(\begin{align*}
\times \, -0.2 \end{align*} t [s] 0.0 -0.1[−0.4 **-0.2** -0.4-0.3 **-0.6** -0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**