Handover trajectory in shared frame, n = 2, Robot: Taker 0.4 0.2 -0.5Z[m]0.2 -1.00.0 Y [m] 0.0 t [s] -0.2 -0.5-0.4Z [m]-0.4-1.0 **-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**