Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 0.2 -0.25 0.1 0.2 0.0 -0.50-0.1E −0.1 × −0.2 Y [m] 0.0 t [s] -0.3 -0.2-0.2Z [m] -0.4-0.4-0.5-0.4-0.6 t [s] t [s] t [s] **True human position Human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**