Handover trajectory in shared frame, n = 2, Robot: Taker 0.4 0.2 -0.5Z [m] 0.3 0.2 0.0 -1.00.1 E **×** −0.2 Y [m] t [s] 0.0 -0.1-0.5Z [m]-0.2 -0.4-0.3-1.0-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**