Handover trajectory in shared frame, n = 3, Robot: Taker **-0.2** 0.4 0.2 Z [m]0.3 0.1 -0.40.2 0.0 0.1 Y[m]**E −0.1** × t [s] 0.0 -0.2 -0.2-0.1**-0.3** Z[m]-0.2 -0.4-0.3 -0.4-0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.10 **Robot plan**