Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.4Z[m]0.3 0.0 0.2 -0.6 0.1 Y [m] t [s] 0.0 -0.1-0.4-0.4Z [m] -0.2**-0.3** -0.6-0.4**-0.6** t [s] t [s] t [s] **True human position Human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.01 **Robot plan**