Handover trajectory in shared frame, n = 7, Robot: Taker 0.4 -0.250.2 Z [m] -0.500.0 0.2 -0.75E -0.2 × Y[m]0.0 t [s] -0.4-0.5-0.2E −0.6 -0.6-0.7-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**