Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 -0.5 Z[m]0.2 0.0 -1.0Y[m]0.0 t [s] -0.5 -0.4**-0.2** Z [m] -0.6-0.4-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**