Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 -0.50.2 Z[m]-1.0 0.2 0.0 Y [m] 0.0 t [s] -0.2-0.4-0.5 Z[m]-1.0 -0.4-0.6 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**