Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 Z[m]-0.40.3 0.1 0.2 0.0 -0.60.1 E -0.1 × -0.2 Y[m]0.0 t [s] -0.1**-0.3** -0.4 -0.2 Z[m]-0.4**-0.3 -0.5** -0.6 -0.4-0.6 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.03 **Robot plan**