Handover trajectory in shared frame, n = 6, Robot: Taker 0.3 0.4 -0.4Z [m] 0.3 0.2 0.2 -0.60.1 0.1 Y [m] 0.0 t [s] 0.0 -0.1-0.1-0.2 -0.4Z[m]-0.2**-0.3 -0.3** -0.6**-0.4** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.00 **Robot plan**