Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 0.2 -0.5Z [m] -1.00.2 0.0 -1.5E −0.2 Y [m] 0.0 t [s] -0.2 -0.5-0.4= -1.0 -0.4-0.6-1.5 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**