Handover trajectory in shared frame, n = 0, Robot: Taker 0.0 0.4 0.2 Z [m] -0.5 0.0 0.2 Y [m] t [s] 0.0 -0.25-0.4[E -0.50 -0.2-0.6-0.4-0.75t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K7 = 0.05 Robot plan**