Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.4 0.2 0.0 Y[m]0.0 t [s] -0.3 -0.4-0.2 Z [m] -0.4**-0.6** -0.4-0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.01 **Robot plan**