Handover trajectory in shared frame, n = 2, Robot: Taker 0.0 0.4 0.2 Z [m] -0.5 0.0 0.2 Y [m] t [s] 0.0 -0.25-0.4-0.2-0.50-0.6-0.4-0.75t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**