Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 0.2 -0.5Z[m]-1.00.2 0.0 \(\frac{\text{\text{E}}}{\times}\) **-0.2** Y[m]0.0 t [s] -0.5 -0.2 -0.4Z[m]-1.0 -0.4-0.6 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**