Handover trajectory in shared frame, n = 3, Robot: Taker -0.25 0.4 0.2 Z[m]0.1 -0.50 0.2 0.0 -0.75-0.1E −0.1 × −0.2 Y[m]0.0 t [s] **-0.3 -0.2** -0.4 Z[m]-0.4-0.5-0.6-0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**