Handover trajectory in shared frame, n = 1, Robot: Taker 0.00 0.4 0.2 -0.25 0.0 0.2 -0.50Y [m] t [s] 0.0 -0.2 -0.4Z[m]**-0.2** -0.4-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K7 = 0.01 Robot plan**