Handover trajectory in shared frame, n = 0, Robot: Taker 0.2 0.4 -0.4Z [m] 0.0 0.2 -0.6-0.2 X [m] Y [m] 0.0 t [s] -0.4-0.4-0.2-0.6-0.48.0-0 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.10 **Robot plan**