Handover trajectory in shared frame, n = 3, Robot: Taker 0.00 0.4 E -0.25 0.2 0.3 0.2 -0.500.0 0.1 Y [m] X [m] t [s] 0.0 -0.2 -0.1-0.2Z [m] **-0.2** -0.4**-0.3** -0.3-0.4-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.10 **Robot plan**