Handover trajectory in shared frame, n = 6, Robot: Taker 0.4 0.2 -0.4Z [m]0.3 -0.60.0 0.2 **8.0**-0.1 Y [m] t [s] 0.0 -0.1-0.4-0.4[E] **-0.6** -0.2**-0.3** -0.6-0.48.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**