Handover trajectory in shared frame, n = 3, Robot: Taker 0.2 0.4 -0.5 Z[m]0.0 0.2 -1.0 -0.2 X [m] Y [m] 0.0 t [s] -0.4-0.2 -0.50Z [m] -0.6-0.75-0.4**-0.8** -1.00t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**