Handover trajectory in shared frame, n = 7, Robot: Taker -0.2 0.4 0.2 Z [m]0.3 0.1 -0.40.2 0.0 0.1 Y [m] **E −0.1** × t [s] 0.0 -0.2 -0.1**-0.3 E** -0.2 -0.2 -0.4-0.3-0.5-0.3t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.08 **Robot plan**