Handover trajectory in shared frame, n = 1, Robot: Taker 0.0 0.4 0.2 [E N **-0.5** 0.3 0.1 0.2 0.0 0.1 Y [m] **E** −0.1 × −0.2 t [s] 0.0 -0.1-0.25-0.3**E −0.50** -0.2 -0.4-0.3 -0.5-0.75-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**