Handover trajectory in shared frame, n = 1, Robot: Taker 0.2 0.4 ≝ −0.5 0.1 0.3 0.0 0.2 -1.0E -0.1 × -0.2 Y[m]t [s] 0.1 0.0 **-0.3** [□ -0.5] -0.1-0.4-0.2 -0.5 -1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**