Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 -0.500.2 -0.750.0 E -0.2 × Y [m] 0.0 t [s] -0.4-0.2 E -0.50 -0.6-0.4-0.75 8.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.03 **Robot plan**