Handover trajectory in shared frame, n = 7, Robot: Taker 0.3 0.4 [−0.4 0.2 0.3 0.1 0.2 -0.6Y[m]0.0 t [s] 0.1 -0.10.0 -0.2 ፱ −0.4 -0.1-0.3**-0.2** -0.6-0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.00 **Robot plan**