Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 ॒ −0.5 0.3 0.1 0.2 0.0 -1.00.1 **E −0.1** × t [s] 0.0 -0.2 -0.1**-0.3** € -0.5 -0.2 -0.4-0.3-0.5-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**