Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 -0.4Z[m]0.3 0.2 0.0 -0.60.1 Y [m] E **×** −0.2 t [s] 0.0 -0.1-0.3 Z[m]**-0.2** -0.4-0.3-0.4-0.6-0.4t [s] t [s] t [s] **True human position Human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.08 **Robot plan**