Handover trajectory in shared frame, n = 2, Robot: Taker 0.2 0.4 -0.5Z [m] 0.0 0.2 -1.0E −0.2 × Y [m] 0.0 t [s] -0.4-0.2-0.50-0.75-0.6-0.4-1.00t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.01 **Robot plan**