Handover trajectory in shared frame, n = 0, Robot: Taker -0.2 0.4 0.2 **E −0.4** 0.3 0.1 0.2 -0.6 0.0 0.1 Y[m]**E −0.1** × t [s] 0.0 -0.2 -0.2-0.1**-0.3** ᠋ −0.4 -0.2 -0.4-0.3 -0.6 -0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** Predicted handover, K7 = 0.08**Robot plan**