Handover trajectory in shared frame, n = 0, Robot: Taker -0.250.4 0.2 **E** −0.50 0.3 0.1 0.2 -0.750.0 0.1 -0.1E −0.1 × −0.2 t [s] 0.0 -0.25-0.1**-0.3** -0.2-0.50-0.4-0.3-0.5-0.75-0.4-0.6t [s] t [s] t [s] **Human position** True human position **Human plan True robot position Robot position** ----- Predicted handover, K8 = -0.00 **Robot plan**