Handover trajectory in shared frame, n = 7, Robot: Taker 0.2 0.4 **-0.2** Z [m] 0.1 0.3 -0.40.2 0.0 -0.60.1 **E −0.1** × **−0.2** Y [m] t [s] 0.0 -0.2-0.1-0.3-0.2**E −0.4** -0.4-0.3 -0.5-0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**