Handover trajectory in shared frame, n = 7, Robot: Taker 0.4 -0.20.2 [m] Z 0.3 0.1 -0.3 0.2 0.0 -0.40.1 -0.1E −0.1 × −0.2 Y [m] t [s] 0.0 -0.1**-0.3** -0.30 -0.2Z[m]-0.4-0.3-0.5-0.35-0.4**-0.6** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.07

Robot plan