Handover trajectory in shared frame, n = 7, Robot: Taker 0.4 0.2 -0.2 E −0.4 0.1 0.2 0.0 -0.6-0.1E −0.1 × −0.2 Y [m] 0.0 t [s] **-0.3** -0.2€ -0.25 -0.4-0.5-0.4-0.30-0.6 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**