Handover trajectory in shared frame, n = 1, Robot: Taker 0.2 0.4 -0.25[H] 0.1 0.3 -0.500.2 0.0 -0.750.1 -0.1**∃ −0.1** × **−0.2** Y [m] t [s] 0.0 -0.1-0.25-0.3-0.2 = **-0.50** -0.4**-0.3** -0.5-0.75-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**