Handover trajectory in shared frame, n = 7, Robot: Taker 0.2 0.4 **E −0.4** N 0.0 0.2 **-0.6** Y[m]0.0 t [s] -0.4**-0.2** -0.4**-0.6** -0.6 -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.00 **Robot plan**