Handover trajectory in shared frame, n = 0, Robot: Taker 0.2 0.4 -0.4[E] N -0.6 0.0 0.2 **E −0.2** × Y [m] 0.0 t [s] -0.4**-0.2** -0.4Z [m] -0.6-0.6-0.4**8.0**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**