Handover trajectory in shared frame, n = 1, Robot: Taker 0.3 0.4 -0.40.2 0.3 0.1 0.2 -0.60.0 0.1 E −0.1 Y [m] t [s] 0.0 -0.2 -0.1[m]-0.4**-0.3** -0.2 -0.4**-0.3** -0.60 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**