Handover trajectory in shared frame, n = 2, Robot: Taker -0.250.4 0.2 ≝ -0.50 0.3 0.1 -0.750.2 0.0 0.1 **E** −0.1 × −0.2 t [s] 0.0 -0.1-0.25**-0.3** ≝ −0.50 -0.2-0.4**-0.3** -0.75-0.5 -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**