Handover trajectory in shared frame, n = 2, Robot: Taker 0.0 0.4 0.2 [E] **-0.5** 0.2 0.0 0.0 t [s] -0.25-0.2-0.4€ -0.50 -0.4-0.75-0.6 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**