Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 -0.250.2 E **−0.50** 0.3 0.2 0.0 -0.750.1 Y [m] 0.0 t [s] -0.1-0.25-0.4-0.2**E −0.50** -0.3 -0.75**-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**