Handover trajectory in shared frame, n = 0, Robot: Taker 0.2 0.4 ≝ −0.4 0.0 0.2 -0.6 E −0.2 Y[m]0.0 t [s] -0.4**-0.2** Z[m]-0.4**-0.6** -0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K7 = 0.09 Robot plan**