Handover trajectory in shared frame, n = 0, Robot: Taker -0.40.4 0.2 E **−0.6** 0.2 0.0 8.0-Y [m] 0.0 t [s] -0.25-0.2 -0.4᠋ −0.50 Ν -0.4-0.6 -0.75t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.02 **Robot plan**