Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 -0.500.3 0.2 0.0 -1.000.1 E **×** −0.2 Y [m] t [s] 0.0 -0.1-0.5-0.2-0.4-0.3 -0.6-0.4-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.00 Robot plan**