Handover trajectory in shared frame, n = 2, Robot: Taker 0.2 0.4 -0.2**E −0.4** 0.1 0.2 0.0 -0.6-0.1**∃ -0.1** × **-0.2** Y[m]0.0 t [s] -0.2-0.3-0.2[m]-0.4 -0.4-0.6-0.5 -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.04 **Robot plan**