Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 -0.250.2 ≝ −0.50 0.3 0.2 -0.750.0 0.1 \(\begin{array}{c} \\ \times \) **-0.2** Y [m] 0.0 t [s] -0.25-0.1-0.2 ੁ −0.50 -0.4**-0.3** -0.75-0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**