Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 -0.20.2 ∃N -0.4 0.3 0.2 0.0 0.1 0.0 t [s] -0.1-0.3-0.2-0.4Z [m] -0.3 -0.4-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**