Handover trajectory in shared frame, n = 0, Robot: Taker 0.00 0.4 0.2 E −0.25 0.3 0.1 0.2 0.0 -0.50 0.1 Y [m] **E** −0.1 × −0.2 t [s] 0.0 -0.1-0.2**-0.3** Z [m] -0.2-0.4**-0.3** -0.3-0.5-0.4-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.01 **Robot plan**