Handover trajectory in shared frame, n = 5, Robot: Taker 0.00 0.2 0.4 Z [m]0.1 0.3 -0.25 0.0 0.2 -0.50E −0.1 × −0.2 Y [m] 0.1 t [s] 0.0 0.0 **-0.3** -0.1Z[m]-0.4-0.2 -0.2 -0.5-0.3 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**