Handover trajectory in shared frame, n = 5, Robot: Taker 0.0 0.2 0.4 ᠋ −0.2 0.1 0.3 0.0 -0.40.2 **E** −0.1 × −0.2 Y [m] t [s] 0.1 0.0 0.0 **-0.3** 든 N **-0.2** -0.1-0.4-0.2 -0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**