Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 **Ξ −0.5** 0.1 0.2 0.0 -1.0E −0.1 × −0.2 Y[m]t [s] 0.0 -0.3-0.5 -0.2 Z[m]-0.4**-0.5** -0.4-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**