Handover trajectory in shared frame, n = 3, Robot: Taker 0.2 0.4 -0.2 Z [m] 0.1 0.3 -0.40.0 0.2 E −0.1 × −0.2 0.1 t [s] 0.0 **-0.3** -0.2 -0.1Z [m] -0.4-0.2 -0.5-0.3**-0.3** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01

**Robot plan**