Handover trajectory in shared frame, n = 5, Robot: Taker 0.2 0.4 **-0.2** 0.1 0.3 0.2 0.0 0.1 **E −0.1** × **−0.2** Y [m] t [s] 0.0 -0.20-0.1-0.3-0.2 **E** -0.25 -0.4-0.3 -0.30 -0.5 -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01

Robot plan