Handover trajectory in shared frame, n = 0, Robot: Taker 0.2 0.4 -0.2 0.1 0.3 0.0 -0.40.2 E -0.1 × -0.2 Y[m]-0.1t [s] 0.1 -0.150.0 -0.3 ᠋ −0.20 -0.1-0.4Ν -0.25 -0.2-0.5 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.04 **Robot plan**