Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 -0.15E -0.20 0.3 0.1 0.2 0.0 -0.25 0.1 **E −0.1** × **−0.2** t [s] 0.0 -0.1-0.10**-0.3** -0.2 ੁ −0.15 -0.4-0.3-0.20 -0.5 -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.09

**Robot plan**