Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 0.2 E −0.4
N 0.3 0.0 0.2 **-0.6** 0.1 Y [m] t [s] 0.0 -0.1-0.4_E **−0.3** -0.2**-0.3** -0.6 -0.4-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**