Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 -0.250.2 [m]0.3 0.1 -0.50 0.2 0.0 -0.750.1 -0.1E −0.1 × −0.2 Y [m] t [s] 0.0 -0.1**-0.3** -0.4**-0.2** Z [m] -0.4-0.6**-0.3** -0.5-0.4**8.0**--0.6 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**