Handover trajectory in shared frame, n = 5, Robot: Taker -0.20.4 0.2 **E -0.4** 0.0 0.2 -0.6E -0.2 × Y [m] 0.0 t [s] -0.4-0.3-0.2∃ -0.4 -0.6-0.4-0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**