Handover trajectory in shared frame, n = 5, Robot: Taker 0.00 0.4 0.2 [H] 0.3 0.1 -0.25 0.2 0.0 -0.500.1 Y [m] **E −0.1** × t [s] 0.0 -0.2 -0.10.0 **-0.3** Z [m] -0.2 -0.4-0.2 **-0.3** -0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.00 **Robot plan**