Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 0.2 -0.25 Z[m]0.1 0.2 -0.500.0 -0.1E −0.1 × −0.2 Y [m] 0.0 t [s] -0.1**-0.3** -0.2ᇀ −0.2 -0.4-0.5-0.3-0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**