Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 0.2 E −0.4
N 0.3 0.1 0.2 0.0 -0.60.1 E -0.1 × -0.2 Y[m]0.0 t [s] -0.1-0.3**-0.3** -0.2 E **−0.4** -0.4**-0.3 -0.5** -0.4-0.6 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.07 **Robot plan**