Handover trajectory in shared frame, n = 5, Robot: Taker 0.0 0.4 0.4 [u] **-0.5** 0.2 0.2 -1.00.0 X [m] Y[m]t [s] 0.0 -0.2-0.2€ -0.5 -0.4-0.6-0.4-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**