Handover trajectory in shared frame, n = 3, Robot: Taker 0.2 0.4 ᠋ −0.4 0.0 0.2 -0.6Y [m] 0.0 t [s] -0.4-0.30 -0.2Z [m] -0.35 **-0.6** -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K5 = 0.05 **Robot plan**