Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 -0.4Z[m]0.2 0.0 -0.6Y[m]0.0 t [s] -0.3-0.4-0.2 [| | **-0.4** -0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.01 **Robot plan**