Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 0.2 -0.50.1 0.2 0.0 -1.0-0.1E −0.1 × −0.2 Y[m]0.0 t [s] **-0.3** -0.2-0.5Z [m] -0.4-0.5-0.4-0.6-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01

Robot plan