Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 0.3 0.0 -0.750.2 0.1 E -0.2 × Y [m] t [s] 0.0 -0.4-0.1-0.4Z[m]**-0.2** -0.6-0.6 **-0.3** -0.48.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.09 **Robot plan**