Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.50든 -0.36 N -0.75 0.2 0.0 -1.00Y [m] 0.0 t [s] -0.2-0.4-0.5 Z [m] -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**