Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 -0.40.2 Z [m] 0.3 -0.6 0.2 0.0 **8.0**-0.1 Y [m] E **×** −0.2 t [s] 0.0 -0.25-0.1ੁ −0.50 **-0.2** -0.4Ν -0.3 -0.75-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**