Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.2 E −**0.2** N −**0.4** 0.1 0.2 0.0 -0.6-0.1E −0.1 × −0.2 Y [m] 0.0 t [s] **-0.3** -0.3-0.2= -0.4 -0.4-0.5-0.4-0.5-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**