Handover trajectory in shared frame, n = 2, Robot: Taker 0.2 0.4 -0.50.0 0.2 -1.00.0 -0.2 E −0.0 · X [m] t [s] -0.4-0.5Z [m]-0.4-0.6-1.0-0.6**-0.8** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**