Handover trajectory in shared frame, n = 4, Robot: Taker 0.2 0.4 -0.25 0.1 0.3 -0.500.0 0.2 E -0.1 × -0.2 Y [m] t [s] 0.1 -0.20.0 -0.3 **E -0.4** -0.1-0.4**-0.6** -0.2 -0.5 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**