Handover trajectory in shared frame, n = 4, Robot: Taker 0.0 0.4 0.2 [u] 7 **-0.5** 0.2 0.0 Y [m] 0.0 t [s] -0.25-0.2-0.4≝ −0.50 -0.4-0.6 -0.75t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**