Handover trajectory in shared frame, n = 4, Robot: Taker -0.2 0.2 0.4 Z [m] 0.1 -0.40.3 0.0 0.2 -0.6E -0.1 × -0.2 Y [m] 0.1 t [s] 0.0 -0.2**-0.3** -0.1**Ξ −0.4** -0.4**-0.2** -0.5-0.6 -0.3 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**