Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.15E -0.13 0.3 0.1 0.2 0.0 -0.250.1 **E −0.1** × **−0.2** t [s] 0.0 -0.1-0.3-0.15 E -0.15 -0.2-0.4-0.3-0.5 -0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K4 = 0.09 **Robot plan**