Handover trajectory in shared frame, n = 4, Robot: Taker 0.2 0.4 -0.25≝ −0.50 0.1 0.2 -0.750.0 Y [m] 0.0 t [s] -0.25-0.3 -0.2ੁ −0.50 -0.4-0.75-0.5-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**