Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.5Z [m]0.2 0.0 -1.00.0 -0.2 **E −0.4** × E -0.2 ≻ t [s] -0.4 -0.6-0.5-0.6Z[m]**-0.8 8.0**--1.0 -1.0-1.00 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**