Handover trajectory in shared frame, n = 4, Robot: Taker 0.3 0.4 -0.3E **−0.4** 0.2 0.3 -0.50.1 0.2 Y [m] 0.0 t [s] 0.1 -0.10.0 -0.2 -0.25-0.1-0.3-0.30-0.2 -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.06 **Robot plan**