Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 0.2 -0.5Z[m]0.2 0.0 -1.0E -0.2 × Y[m]0.0 t [s] -0.2-0.4E -0.50 -0.4N **−0.75** -0.6-1.00t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**