Handover trajectory in shared frame, n = 4, Robot: Taker 0.3 0.4 E −0.4
N 0.3 0.2 0.2 0.1 -0.60.1 Y [m] 0.0 t [s] 0.0 -0.1-0.1-0.2 -0.30 E −0.30 E −0.35 -0.2**-0.3** -0.3-0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**