Handover trajectory in shared frame, n = 4, Robot: Taker 0.4 -0.2 0.2 Z [m]0.3 0.1 -0.40.2 0.0 0.1 Y [m] **E −0.1** × t [s] 0.0 -0.2 -0.1**-0.3** ᠍ −0.2 -0.2 -0.4**-0.3 -0.5** -0.3t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01 **Robot plan**