Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 -0.25 0.2 E −0.50N −0.75 0.3 0.2 -0.750.0 0.1 \(\text{\(\) \(Y [m] 0.0 t [s] -0.1-0.25-0.2 -0.50E -0.50 N -0.75 -0.4-0.3 -0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**