Handover trajectory in shared frame, n = 3, Robot: Taker 0.4 -0.25 0.2 = -0.50 0.2 0.0 -0.75E -0.2 × Y [m] 0.0 t [s] -0.4-0.4-0.2 **E** −0.6 -0.6-0.4**8.0**t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**