Handover trajectory in shared frame, n = 4, Robot: Taker 0.2 0.4 -0.5Z [m] 0.3 0.0 0.2 -1.00.1 E −0.2 × t [s] 0.0 -0.1-0.4-0.5-0.2 Z [m] -0.3**-0.6** -0.4 -1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**