Handover trajectory in shared frame, n = 0, Robot: Taker 8.0 0.2 -0.5 Z[m]0.1 0.6 -1.00.0 0.4 X [m] E -0.1 ≻ -0.2 t [s] 0.2 -0.30.0 -0.5 -0.4-0.2 -1.0-0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01 **Robot plan**