Handover trajectory in shared frame, n = 6, Robot: Taker 0.4 0.2 -0.500.3 -0.750.0 0.2 E -0.2 × Y [m] 0.1 t [s] 0.0 -0.4-0.1E -0.50 **-0.2** -0.6-0.75-0.38.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**