Handover trajectory in shared frame, n = 6, Robot: Taker -0.20.2 0.4 = -0.4 0.0 0.2 -0.2 X [m] Y [m] 0.0 t [s] -0.4-0.2-0.6-0.4-0.4**-0.8** 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**