Handover trajectory in shared frame, n = 6, Robot: Taker 0.3 0.4 ᠋ −0.4 0.2 0.3 0.1 0.2 **-0.6** Y[m]0.0 t [s] 0.1 -0.10.0 -0.2 ᠍ −0.4 -0.1-0.3**-0.2** -0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**