Handover trajectory in shared frame, n = 2, Robot: Taker -0.2 0.4 0.2 **E -0.4** 0.1 0.2 0.0 -0.6-0.1E −0.1 × −0.2 Y[m]0.0 t [s] **-0.3** -0.2-0.4 Z[m]-0.4-0.5**-0.6** -0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01 **Robot plan**