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