Handover trajectory in shared frame, n = 6, Robot: Taker 0.00 0.4 0.2 -0.25 0.0 0.2 -0.50Y[m]t [s] 0.0 -0.4-0.1-0.2-0.2 -0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**