Handover trajectory in shared frame, n = 6, Robot: Taker 0.00 0.4 0.2 ᠋ −0.25 0.3 0.1 0.2 0.0 -0.500.1 -0.1Y [m] E −0.1 × −0.2 t [s] 0.0 0.0 **-0.3** -0.1E N -0.2 -0.4-0.2-0.5-0.3-0.6 -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**