Handover trajectory in shared frame, n = 6, Robot: Taker 0.2 0.4 ᠋ −0.4 0.0 0.2 -0.6Y [m] 0.0 t [s] -0.4-0.2**-0.6** -0.4-0.35t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.08 **Robot plan**