Handover trajectory in shared frame, n = 6, Robot: Taker -0.2 0.4 0.2 Z [m] 0.3 0.1 -0.4 0.2 0.0 0.1 **E −0.1** × t [s] 0.0 -0.2 -0.1**-0.3** -0.2Z [m] -0.2-0.4**-0.3** -0.5-0.3t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**