Handover trajectory in shared frame, n = 6, Robot: Taker 0.4 -0.40.2 Z[m]0.3 -0.6 0.2 0.0 0.1 Y [m] \(\begin{align*}
\times \, -0.2 \end{align*} t [s] 0.0 -0.1-0.4Z [m] **-0.2** -0.4-0.3 -0.6-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**