Handover trajectory in shared frame, n = 3, Robot: Taker 0.3 -0.30.4 ᠋ −0.4 0.2 0.3 -0.50.1 0.2 Y [m] 0.0 t [s] 0.1 -0.10.0 -0.2 [−0.3 -0.1-0.3-0.2 -0.4-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.07 **Robot plan**