Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 든 **-0.25** N 0.2 0.0 -0.50Y [m] 0.0 t [s] -0.2 -0.4€ -0.4 -0.4-0.6**-0.6** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K6 = 0.01 **Robot plan**