Handover trajectory in shared frame, n = 1, Robot: Taker -0.2 0.4 0.2 ᠋ −0.4 0.0 0.2 -0.6E -0.2 × Y [m] 0.0 t [s] -0.4-0.2ੁ −0.45 -0.6-0.4-0.50t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K6 = 0.01 **Robot plan**