Handover trajectory in shared frame, n = 0, Robot: Taker 0.2 0.4 -0.2 [ 일 **~ -0.4** 0.1 0.3 0.2 0.0 0.1 -0.1**∃ −0.1** × **−0.2** Y [m] t [s] 0.0 -0.2-0.1-0.3-0.2 [m] -0.3 -0.4**-0.3** -0.5-0.4-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K5 = 0.09 **Robot plan**