Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 -0.40.2 [일 지 **-0.6** 0.2 0.0 Y[m]0.0 t [s] -0.4-0.2-0.4Z[m]-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**