Handover trajectory in shared frame, n = 7, Robot: Taker 0.4 -0.250.2 든 이 **-0.50** 0.1 0.2 0.0 -0.75**E** −0.1 × −0.2 Y [m] t [s] 0.0 -0.4-0.3-0.2 Z[m]-0.4-0.6 -0.5 -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**