Handover trajectory in shared frame, n = 6, Robot: Taker 0.2 0.4 -0.4드 이 **-0.6** 0.0 0.2 -0.2 E **−0.4** Y [m] 0.0 t [s] -0.40-0.2-0.6E **−0.45 -0.8** -0.4-0.500 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**