Handover trajectory in shared frame, n = 2, Robot: Taker -0.50.4 0.2 든 지 **-1.0** 0.3 0.0 0.2 E -0.2 × Y [m] 0.1 t [s] 0.0 -0.4-0.5-0.1[ 된 **P -1.0 -0.2** -0.6-0.3**-0.8** 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**