Handover trajectory in shared frame, n = 6, Robot: Taker 0.4 -0.25 0.2 [<u>m</u>] \_\_ -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 [ 일 **-0.6** -0.4-0.5 -0.4t [s] t [s] t [s] **True human position Human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**