Handover trajectory in shared frame, n = 5, Robot: Taker 0.4 0.2 -0.25든 **-0.25** 돈 **-0.50** 0.2 0.0 -0.75Y [m] 0.0 t [s] -0.2-0.4 -0.4Z[m]-0.6 -0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**