Handover trajectory in shared frame, n = 6, Robot: Taker 0.4 0.2 0.0 든 지 **-0.2** 0.2 0.0 Y [m] 0.0 t [s] 0.0 -0.2 -0.4Z[m]-0.2 -0.4-0.6-0.4t [s] t [s] t [s] **True human position Human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**