Handover trajectory in shared frame, n = 2, Robot: Taker 0.2 0.4 **-0.5** [본 **P -1.0** 0.0 0.2 0.0 -0.2 Y [m] X [m] t [s] -0.4-0.2 -0.5∃N -1.0 -0.4-0.6-0.60 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.00 **Robot plan**