Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 -0.5 0.2 드 -0.5 돈 -1.0 0.2 0.0 Y [m] 0.0 t [s] -0.2**-0.5** -0.4∃N -1.0 -0.4-0.6 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**