Handover trajectory in shared frame, n = 3, Robot: Taker 0.2 0.4 -0.5 Z[m]0.0 -1.00.2 -0.2 X [m] Y[m]0.0 t [s] -0.4-0.5-0.2 [일 지 **-1.0** -0.6-0.4**-0.8** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**