Handover trajectory in shared frame, n = 0, Robot: Taker 0.4 0.2 -0.25든 **-0.25** 진 **-0.50** 0.1 0.2 0.0 -0.1E −0.1 × −0.2 Y [m] 0.0 t [s] -0.3-0.2-0.4 Z[m]-0.4-0.6 -0.5-0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K7 = 0.04 **Robot plan**