Handover trajectory in shared frame, n = 5, Robot: Taker -0.250.4 0.2 E **−0.50** 0.3 0.1 0.2 0.0 -0.750.1 -0.1Y [m] E −0.1 × −0.2 t [s] 0.0 **-0.3** -0.1-0.4드 -0.4 진 -0.6 -0.4**-0.2** -0.5-0.3-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K8 = 0.01 **Robot plan**