Handover trajectory in shared frame, n = 4, Robot: Taker 0.2 0.4 -0.5Z [m] 0.0 0.2 -1.0 -0.2 0.0 t [s] -0.2 -0.4-0.5든 N **-1.0** -0.4-0.6-0.6 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**