Handover trajectory in shared frame, n = 2, Robot: Taker 0.4 0.2 -0.5 든 **-0.5** 돈 **-1.0** 0.2 0.0 E -0.2 × Y [m] 0.0 t [s] -0.5-0.2-0.4Z[m]-1.0-0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**