Handover trajectory in shared frame, n = 1, Robot: Taker 0.4 0.2 -0.25트 **-0.50** 0.1 0.2 0.0 -0.75-0.1E −0.1 × −0.2 Y [m] 0.0 t [s] -0.25**-0.3** -0.2-0.50-0.4-0.5-0.75-0.4-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**