Handover trajectory in shared frame, n = 6, Robot: Taker 0.4 0.2 -0.40.2 0.0 E -0.2 × Y[m]0.0 t [s] -0.4-0.4-0.2 된 기 **-0.6** -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**