Handover trajectory in shared frame, n = 7, Robot: Taker 0.2 0.4 **-0.2** 된 지 **-0.4** 0.1 0.3 0.0 0.2 E -0.1 × -0.2 Y [m] 0.1 t [s] 0.0 -0.2**-0.3** -0.1Z [m] -0.4-0.4**-0.2** -0.5**-0.3** t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.00 **Robot plan**