Handover trajectory in shared frame, n = 4, Robot: Taker 0.2 0.4 [필 **-0.5** 임 0.0 0.2 -1.0-0.2 X [m] 0.0 t [s] -0.4-0.2-0.5Z [m] **-0.6** -0.4-0.8-1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**