Handover trajectory in world frame, n = 7, Robot: Taker 1.6 0.0 Z [m] 0.2 **1.4** -0.2 0.0 1.2 **E** 1.2 × 1.0 E **> −0.2** t [s] 0.0 8.0 -0.4[ 일 이 **-0.2** 0.6 **-0.6** 0.4 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**