Handover trajectory in world frame, n = 0, Robot: Taker 1.8 0.0 Z[m]0.2 1.6 1.4 -0.20.0 **∃** 1.2 × 1.0 E **> −0.2** t [s] 0.0 0.8 -0.4[ 지 **-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, K7 = 0.02**Robot plan**