Handover trajectory in world frame, n = 4, Robot: Taker 0.0 0.4 1.8 Z [m] 1.6 -0.50.2 1.4 0.0 Y [m] **E** 1.2 t [s] -0.21.0 -0.25든 이 **-0.50** 8.0 -0.40.6 -0.6 -0.75t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**