Handover trajectory in world frame, n = 5, Robot: Taker 0.4 0.00 Z [m] **1.4** 0.2 -0.251.2 0.0 Y [m] **≦ 1.0** × t [s] -0.2 8.0 0.0 트 지 **-0.1** -0.40.6 **-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 = 0.01 Robot plan**