Handover trajectory in world frame, n = 0, Robot: Taker 1.8 0.4 0.0 [일 지 **-0.5** 1.6 0.2 **1.4** 0.0 **E** 1.2 × 1.0 Y [m] t [s] -0.20.0 8.0 = -0.5 -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 = 0.00 Robot plan**