Handover trajectory in world frame, n = 7, Robot: Taker **1.8** 0.4 0.25 [m]1.6 0.00 0.2 1.4 -0.250.0 **E ≻ −0.2 ∃** 1.2 × 1.0 t [s] 0.0 0.8 -0.4[된 **N -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 = 0.01 **Robot plan**