Handover trajectory in world frame, n = 1, Robot: Taker 0.0 1.6 [ 인 **-0.2** 0.2 1.4 0.0 1.2 **∃** 1.2 × 1.0 E **> −0.2** t [s] 0.0 8.0 -0.4트 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, K7 = 0.05 **Robot plan**