Handover trajectory in world frame, n = 1, Robot: Taker 0.4 1.6 0.0 Z[m]0.2 1.4 -0.50.0 1.2 **≦ 1.0** × **1.0 E ≻ −0.2** t [s] 0.00 0.8 -0.4트 **-0.25** 0.6 Ν -0.6 -0.500.4 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**