Handover trajectory in world frame, n = 0, Robot: Taker -0.11.6 Z [m] 0.2 -0.21.4 -0.30.0 \(\sum_{\text{\(\text{\\chint{\(\text{\(\text{\\chint{\(\text{\\chint{\(\text{\(\text{\(\text{\(\text{\(\text{\\chint{\(\text{\\chint{\(\text{\\chint{\(\text{\\chint{\(\text{\\chini{\\chint{\\chint{\\chint{\\chint{\\chint{\\chint{\\chint{\\chini{\\chint{\\chint{\\chint{\\chint{\\chint{\\chint{\\chint{\\chini{\\chint{\\chint{\\chint{\\chint{\\chint{\\chint{\\chint{\\chini{\\chint{\\chint{\\chint{\\chint{\\chint{\\chini{\\chint{\\chini{\\chint{\\chint{\\chini\chini{\\chini{\\chini\}\chini\chini{\\chini{\\chini{\\chini{\\chini{\\chini{\\c **E ≻ −0.2** t [s] -0.10.8 드 N **-0.2** -0.40.6 **-0.6** -0.3t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ---- Predicted handover, K5 = 0.03 **Robot plan**