Handover trajectory in world frame, n = 1, Robot: Taker 1.8 0.0 1.6 0.2 1.4 0.0 **∃** 1.2 × 1.0 **E ≻ −0.2** t [s] 0.0 0.8 [진 **-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 = 0.01 **Robot plan**