Handover trajectory in world frame, n = 5, Robot: Taker 1.8 0.4 0.0 Z [m] 1.6 0.2 1.4 -0.50.0 1.2 **∃** 1.0 **E > −0.2** t [s] 0.8 0.0 -0.4[ 진 **-0.5** 0.6 0.4 -0.6 0.2 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**