Handover trajectory in world frame, n = 4, Robot: Taker 0.0 1.6 [인 **-0.5** 0.2 1.4 0.0 1.2 **∃** 1.2 × 1.0 **E → -0.2** t [s] 0.0 0.8 -0.4□N -0.5 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, K8 = 0.01 **Robot plan**