Handover trajectory in world frame, n = 4, Robot: Taker 1.6 0.2 0.00 진 -0.05 1.4 0.0 1.2 = -0.2 ≻ t [s] 0.05 8.0 -0.4Z [m]0.00 0.6 -0.6 0.4 -0.05t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.10 **Robot plan**