Handover trajectory in world frame, n = 0, Robot: Taker 0.6 0.0 1.8 Z [m] 0.4 1.6 -0.50.2 1.4 **E** 1.2 Y[m]0.0 t [s] × 1.0 -0.2 -0.25든 -0.23 진 -0.50 8.0 -0.40.6 -0.6-0.75t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.02 **Robot plan**