Handover trajectory in world frame, n = 6, Robot: Taker 0.0 1.6 [E] N -0.2 0.2 1.4 0.0 \(\sum_{\text{\subset}} \) 1.2 \(\text{\text{\subset}} \) 1.0 **E ≻ -0.2** t [s] 0.0 0.8 Z [m] -0.40.6 -0.1-0.6 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**