Handover trajectory in world frame, n = 5, Robot: Taker 1.8 0.0 Z [m]0.2 **1.6** -0.2 **1.4** 0.0 **≦** 1.2 × 1.0 **E → -0.2** t [s] 8.0 -0.4 $[\Pi]$ -0.10.6 -0.60.4 -0.2t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**