Handover trajectory in world frame, n = 6, Robot: Taker 0.4 1.8 0.00 Z [m] 1.6 0.2 -0.251.4 0.0 Y [m] \( \brace{\mathbb{E}}{\times} \) **1.2** × 0 t [s] -0.2 1.0 0.1 0.8 [m]-0.40.0 0.6 -0.1-0.6 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**