Handover trajectory in world frame, n = 0, Robot: Taker 0.0 1.2 0.6 Z [m] 1.0 -0.50.4 8.0 0.6 Y [m] 0.2 t [s] 0.4 0.0 0.0 0.2 [E] **-0.5** 0.0 -0.2-0.2-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01 **Robot plan**