Handover trajectory in world frame, n = 5, Robot: Taker 0.0 0.4 1.8 □N -0.2 1.6 0.2 1.4 0.0 Y [m] **E** 1.2 t [s] -0.2 1.0 -0.1Z [m] 8.0 -0.40.6 -0.2-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**