Handover trajectory in world frame, n = 1, Robot: Taker 0.0 Z [m] 1.6 0.2 1.4 -0.50.0 \(\frac{\E}{\E}\) 1.2 × 1.0 **E → -0.2** t [s] 0.00 0.8 -0.4**E** −0.25 0.6 Ν -0.50-0.6 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**