Handover trajectory in world frame, n = 0, Robot: Taker 0.0 1.6 E -0.1 0.2 1.4 0.0 -0.21.2 E **≻ −0.2** t [s] 0.1 8.0 -0.4Z[m]0.0 0.6 **-0.6** -0.1t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.08 **Robot plan**