Handover trajectory in world frame, n = 1, Robot: Taker 1.8 0.4 -0.1Z[m]1.6 0.2 -0.21.4 -0.30.0 \(\sum_{\text{\tinc{\tint{\text{\ti}\}\\ \text{\te}\}\text{\texi}\text{\\text{\text{\text{\text{\text{\text{\text{\text{\text{\texi}\text{\text{\texi}\tex{ Y [m] t [s] -0.2 0.0 0.8 E N -0.1 -0.40.6 **-0.6** 0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.01 **Robot plan**