Handover trajectory in world frame, n = 1, Robot: Taker 1.8 0.4 0.0 Z [m] 1.6 0.2 -0.51.4 0.0 **E** 1.2 × 1.0 Y [m] t [s] -0.2 0.0 0.8 [E] N **-0.5** -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, K8 = 0.01 **Robot plan**