Handover trajectory in world frame, n = 1, Robot: Taker 1.6 0.0 0.2 든 지 **-0.1** 1.4 0.0 1.2 -0.2 t [s] 0.0 8.0 -0.4EN −0.1 0.6 -0.60.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.03 **Robot plan**