Handover trajectory in world frame, n = 1, Robot: Taker 1.6 트 **-0.2** N 0.2 1.4 -0.40.0 **E ≻ −0.2** t [s] 0.8 <u>-0.2</u> N -0.40.6 **-0.6** -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.07 **Robot plan**