Handover trajectory in world frame, n = 6, Robot: Taker 0.4 0.00 Z[m]**1.4** 0.2 -0.25 1.2 -0.500.0 Y [m] **≦ 1.0** × t [s] -0.2 8.0 -0.2Z [m]-0.40.6 -0.4**-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**