Handover trajectory in world frame, n = 1, Robot: Taker 0.00 0.4 1.8 **E −0.25** 1.6 0.2 -0.501.4 0.0 Y [m] t [s] -0.2 1.0 -0.2Z [m] 8.0 -0.4-0.40.6 **-0.6** -0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.07 **Robot plan**