Handover trajectory in world frame, n = 5, Robot: Taker 1.6 0.2 0.00 든 0.00 돈 -0.05 1.4 0.0 1.2 -0.2 t [s] 8.0 -0.4Z[m]0.00 0.6 -0.6 -0.050.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.08 **Robot plan**