Handover trajectory in world frame, n = 7, Robot: Taker 0.4 0.00 [ ] **1.4** 0.2 **N −0.25** 1.2 0.0 Y [m] **≦ 1.0** × t [s] -0.2 8.0 E −0.2
N -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**