Handover trajectory in world frame, n = 0, Robot: Taker 1.6 0.4 0.0 [E] N -0.2 1.4 0.2 1.2 -0.40.0 Y [m] t [s] -0.2 8.0 0.0 Z[m]-0.4-0.20.6 -0.6-0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K7 = 0.04 Robot plan**