Handover trajectory in world frame, n = 0, Robot: Taker 1.6 0.0 0.4 **1.4** 0.2 1.2 0.0 Y [m] t [s] -0.2 8.0 -0.25-0.4-0.500.6 -0.75-0.6 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**