Handover trajectory in world frame, n = 3, Robot: Taker 0.0 1.6 든 N **-0.2** 0.2 **1.4** 0.0 **∃** 1.2 × 1.0 **E → -0.2** t [s] 0.05 8.0 -0.4Z[m]0.00 0.6 -0.6 0.4 -0.05t [s] t [s] t [s] **True human position Human position Human plan True robot position Robot position Predicted handover, K6 = 0.01 Robot plan**