Handover trajectory in world frame, n = 6, Robot: Taker 0.4 0.0 **1.8** Z [m]1.6 0.2 -0.2 **1.4** 0.0 Y [m] **E** 1.2 t [s] -0.2 1.0 0.0 Z [m] 8.0 -0.40.6 -0.1-0.6t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position Predicted handover, K8 = 0.01 Robot plan**