Handover trajectory in world frame, n = 2, Robot: Taker 0.4 1.8 <u>E</u> -0.2 0.2 1.6 -0.41.4 0.0 **E −0.2 Ξ 1.2** × t [s] 1.0 0.8 -0.4-0.2 0.6 -0.6-0.40.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01 **Robot plan**