Handover trajectory in world frame, n = 4, Robot: Taker 0.2 1.6 Z [m] 0.2 0.0 **1.4** -0.20.0 \(\frac{\E}{\E}\) 1.2 × 1.0 E **> −0.2** t [s] 0.0 0.8 -0.4Z [m] -0.10.6 **-0.6** -0.20.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**