Handover trajectory in world frame, n = 6, Robot: Taker 1.6 ᠍ −0.2 0.2 **1.4** 0.0 -0.41.2 **∃ 1.2** × **1.0** E **> −0.2** t [s] 0.0 0.8 -0.4 Z [m] -0.20.6 -0.6 0.4 -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**