Handover trajectory in world frame, n = 0, Robot: Taker 1.8 0.4 Z[m]0.0 1.6 0.2 1.4 -0.50.0 **∃** 1.2 × 1.0 [m] ≻ t [s] -0.2 0.00 8.0 -0.4-0.250.6 -0.6 -0.500.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** Predicted handover, K7 = 0.05**Robot plan**