Handover trajectory in world frame, n = 3, Robot: Taker 0.0 0.4 1.8 ∃ -0.5 1.6 0.2 **1.4** -1.00.0 Y [m] **E** 1.2 t [s] -0.2 1.0 E −0.5
N 8.0 -0.40.6 -0.6 -1.0t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**