Handover trajectory in world frame, n = 4, Robot: Taker 0.4 0.00 Z [m] **1.4** 0.2 -0.251.2 0.0 Y [m] **≦ 1.0** × t [s] -0.2 0.8 -0.1Z [m] -0.40.6 -0.2**-0.6** -0.30.4 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**