Handover trajectory in world frame, n = 2, 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] 0.8 0.0 -0.4Z [m]0.6 **-0.6** -0.2 0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.02 **Robot plan**