Handover trajectory in world frame, n = 3, Robot: Taker -0.11.6 Z[m]0.2 -0.2**1.4** -0.30.0 1.2 **≦ 1.2** × **1.0** E **> −0.2** t [s] 0.0 0.8 -0.4 Z [m] 0.6 -0.2 **-0.6** 0.4 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**