Handover trajectory in world frame, n = 2, Robot: Taker 1.8 0.4 0.0 Z [m] 1.6 0.2 1.4 -0.50.0 **E** 1.2 × 1.0 Y [m] t [s] -0.20.00 0.8 **E** −0.25 -0.40.6 Ν -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 = 0.01 **Robot plan**