Handover trajectory in world frame, n = 2, Robot: Taker 0.0 1.8 0.4 = **-0.5** 1.6 0.2 -1.01.4 0.0 \(\brace{\mathbb{E}}{\times} \) **1.2** × Y[m]t [s] -0.2 1.0 0.8 -0.5-0.40.6 -0.6-1.00.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**