Handover trajectory in world frame, n = 3, Robot: Taker 1.8 0.0 Z [m]0.2 1.6 1.4 -0.50.0 **∃** 1.2 × 1.0 E **> −0.2** t [s] 0.0 0.8 -0.4Z [m] 0.6 -0.5-0.60.4 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**