Handover trajectory in world frame, n = 4, Robot: Taker 0.4 0.0 1.6 Z [m]0.2 1.4 -0.50.0 1.2 **∃** × **1.0** E ≻ **-0.2** t [s] 0.0 0.8 Z [m] -0.40.6 -0.5-0.6 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**