Handover trajectory in world frame, n = 3, Robot: Taker 0.0 0.4 1.8 Z[m]1.6 0.2 -0.51.4 0.0 Y [m] \(\brace{\mathbb{E}}{\times} \) **1.2** × t [s] -0.2 1.0 -0.20.8 -0.40.6 -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**