Handover trajectory in world frame, n = 1, Robot: Taker 0.0 **1.6** = -0.1 0.2 1.4 -0.20.0 1.2 E **≻ −0.2** t [s] 0.0 8.0 -0.4= -0.1 0.6 **-0.6** -0.2t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.03 **Robot plan**