Handover trajectory in world frame, n = 5, Robot: Taker 1.8 0.0 0.4 □N -0.2 1.6 0.2 1.4 0.0 **∃** 1.2 × 1.0 Y [m] t [s] -0.20.8 Z[m]-0.40.0 0.6 -0.60.4 -0.1t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**