Handover trajectory in world frame, n = 3, Robot: Taker 0.4 0.00 Z [m] 1.4 0.2 -0.251.2 0.0 Y [m] **≦ 1.0** × t [s] -0.2 8.0 -0.1E N −0.2 -0.40.6 **-0.6** 0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**