Handover trajectory in world frame, n = 2, Robot: Taker 0.4 1.8 0.0 Z [m] 1.6 0.2 1.4 -0.50.0 **∃** 1.2 × 1.0 E ≻ -0.2 t [s] 0.00 0.8 **E** −0.25 -0.4Ν 0.6 -0.6 -0.500.4 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**