Handover trajectory in world frame, n = 7, Robot: Taker 0.1 1.6 Z [m]0.2 0.0 **1.4** 0.0 -0.11.2 **∃** 1.2 × 1.0 E **> −0.2** t [s] 0.00 8.0 -0.4Z[m]0.6 -0.05-0.6 0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.07 **Robot plan**