Handover trajectory in world frame, n = 4, Robot: Taker 1.8 0.4 0.0 Z [m] 1.6 0.2 1.4 -0.50.0 \(\sum\_{\text{\subset}} \) 1.2 \(\text{\text{\text{\subset}}} \) 1.0 Y [m] t [s] -0.2 0.00 0.8 -0.4᠋ −0.25 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**