Handover trajectory in world frame, n = 2, Robot: Taker 0.4 1.6 0.0 Z[m]**1.4** 0.2 -0.51.2 0.0 \(\frac{\text{\text{E}}}{\times}\) **1.0 E ≻ −0.2** t [s] 0.0 0.8 -0.4Z [m] 0.6 -0.6-0.5t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K8 = 0.01 **Robot plan**