Handover trajectory in world frame, n = 3, Robot: Taker 0.4 **1.6** 0.0 Z[m]1.4 0.2 -0.2 1.2 0.0 Y [m] t [s] -0.2 8.0 0.0 Z [m] -0.40.6 -0.6 -0.1t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** Predicted handover, K7 = 0.10**Robot plan**