Handover trajectory in world frame, n = 1, Robot: Taker 0.4 0.0 1.8 □ -0.2 0.2 1.6 1.4 -0.40.0 **Ξ 1.2** × **E ≻ −0.2** t [s] 1.0 0.8 -0.4-0.15Z [m] 0.6 **-0.6** -0.200.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K6 = 0.01 **Robot plan**