Handover trajectory in world frame, n = 7, Robot: Taker 0.0 1.6 [E] N -0.2 0.2 **1.4** 0.0 -0.4**∃** 1.2 × 1.0 E **> −0.2** t [s] 0.0 8.0 -0.4Z [m] -0.2 0.6 -0.6 0.4 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**