Handover trajectory in world frame, n = 2, Robot: Taker 1.6 0.00 Z [m]0.2 1.4 -0.050.0 1.2 **E → -0.2** t [s] 8.0 -0.4Z [m] 0.00 0.6 -0.6 -0.05t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K4 = 0.08 **Robot plan**