Handover trajectory in world frame, n = 2, Robot: Taker 0.4 1.6 0.0 Z [m] 1.4 -0.2 0.2 -0.41.2 0.0 \(\text{\\chi}\)}}}\end{\(\text{\\\exitings}}}\end{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\(\text{\\chi}\)}}}\end{\(\text{\exitings}}}}\end{\(\text{\(\text{\\chi}\)}}\end{\(\text{\\\exitings}}}\end{\(\text{\\\exitings}}}\end{\(\text{\(\text{\\chi}\)}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}\end{\(\text{\\exitings}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}\end{\\exitings}}\end{\(\text{\\exitings}}}\end{\(\text{\\exitings}}\end{\\exitings}}\end{\\exitings}}\end{\\\exitings}\end{\\exitings}}\end{\\\exitings}}\end{\\\exitings}\end{\\exitings}}\end{\\\exitings}\end{\\exitings}\end{\\exitings}}\end{\\exitings}\end{\\exitings}\end{\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\exitings}\end{\\end{\\exitings}}\end{\\exitings}\end{\\exitings}\end{\\exitings}\end{\\exitings}}\end{\\exitings}\end{\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\end{\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\\\exitings}\end{\ Y [m] t [s] -0.2 0.0 8.0 ≝ −0.2 -0.4Ν 0.6 **-0.6** -0.4t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.04 **Robot plan**