Handover trajectory in world frame, n = 3, Robot: Taker 1.8 0.0 E N **−0.2** 1.6 0.2 1.4 0.0 **∃** 1.2 × 1.0 **E ≻ −0.2** t [s] 0.00 0.8 든 N **-0.05** -0.40.6 **-0.6** 0.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K5 = 0.05 **Robot plan**