Handover trajectory in world frame, n = 6, Robot: Taker 1.6 0.0 Z [m] 0.2 **1.4** -0.2 0.0 1.2 **∃** 1.2 × 1.0 E **> −0.2** t [s] 8.0 -0.4[E **0.1** N 0.6 0.0 -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**