Handover trajectory in world frame, n = 7, Robot: Taker 1.8 0.0 0.2 Z [m]**1.6** -0.2 1.4 0.0 **≦** 1.2 × 1.0 E **> −0.2** t [s] 8.0 -0.4E −0.05
N 0.6 -0.6-0.100.4 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**