Handover trajectory in world frame, n = 2, Robot: Taker **1.8** 0.4 Z [m] 0.0 1.6 0.2 1.4 -0.50.0 **∃** 1.2 × 1.0 **\(\bar{\E}\) \(-0.2\)** t [s] 0.00 0.8 -0.4E -0.25 0.6 -0.6-0.500.4 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**