Handover trajectory in world frame, n = 0, Robot: Taker 0.0 1.6 Z [m]0.2 **1.4** -0.50.0 1.2 **∃** × **1.0 E → -0.2** t [s] 0.00 8.0 -0.4**E −0.25** 0.6 -0.50-0.6 0.4 t [s] t [s] t [s] **Human position** True human position **Human plan True robot position Robot position** ---- Predicted handover, K8 = -0.00 **Robot plan**