Handover trajectory in world frame, n = 5, Robot: Taker 0.00 1.6 © E N −0.25 0.2 1.4 0.0 1.2 **E** 1.2 × 1.0 E **> −0.2** t [s] 0.0 8.0 -0.4**E** −0.2 0.6 **-0.6** -0.40.4 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**