Handover trajectory in world frame, n = 5, Robot: Taker -0.11.4 0.2 ᠍ −0.2 1.2 **-0.3** 0.0 **∃ 1.0** × E **> -0.2** t [s] **8.0** -0.05-0.4Z[m]0.6 -0.10-0.60.4 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K7 = 0.01 **Robot plan**