Handover trajectory in world frame, n = 1, Robot: Taker 1.8 0.4 0.25 [m] 1.6 0.00 0.2 1.4 -0.250.0 **∃** 1.2 × 1.0 **E ≻ −0.2** t [s] 0.8 0.0 -0.4Z[m]0.6 -0.2**-0.6** 0.4 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**