Handover trajectory in world frame, n = 7, Robot: Taker 0.4 0.00 1.8 © N **−0.25** 0.2 1.6 1.4 0.0 \( \brace{\mathbb{E}}{\times} \) **1.2** × **E ≻ −0.2** t [s] 1.0 -0.20.8 -0.4Z[m]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**