Handover trajectory in world frame, n = 3, Robot: Taker 0.05 1.6 Z[m]0.2 0.00 1.4 -0.050.0 1.2 **E → -0.2** t [s] 8.0 -0.4€ 0.05 0.6 -0.6 0.00 t [s] t [s] t [s] **Human position True human position Human plan True robot position Robot position** ----- Predicted handover, K3 = 0.04 **Robot plan**