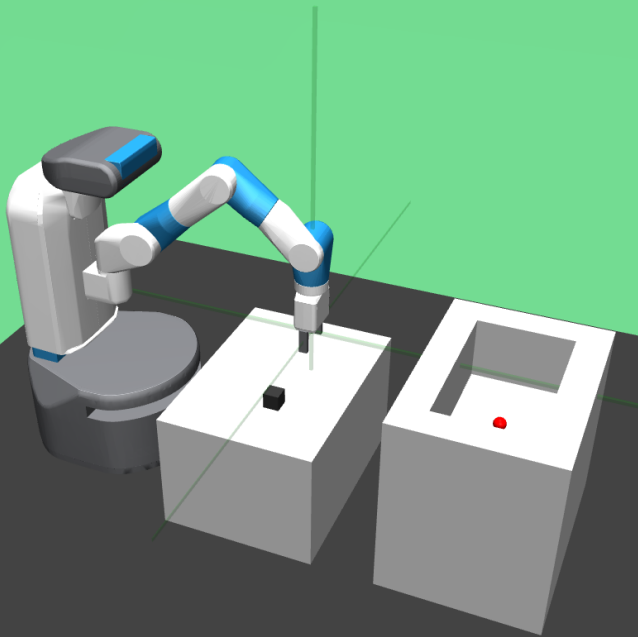


Run speed = 1.000 x real time	[S]lower, [F]aster
Render every frame	On
Switch camera (#cams = 5)	[Tab] (camera ID = -1)
Contact forces	On
Reference frames	On
Transparent	Off
Display Mujoco bodies	On
Stop	[Space]
Advance simulation by one step	[right arrow]
Hide Menu	
Record Video (Off)	
Capture frame	
Start ipdb	
Toggle geomgroup visibility	0-4



FPS 29
Solver iterations 3

Step 440
timestep 0.00200
n_substeps 20