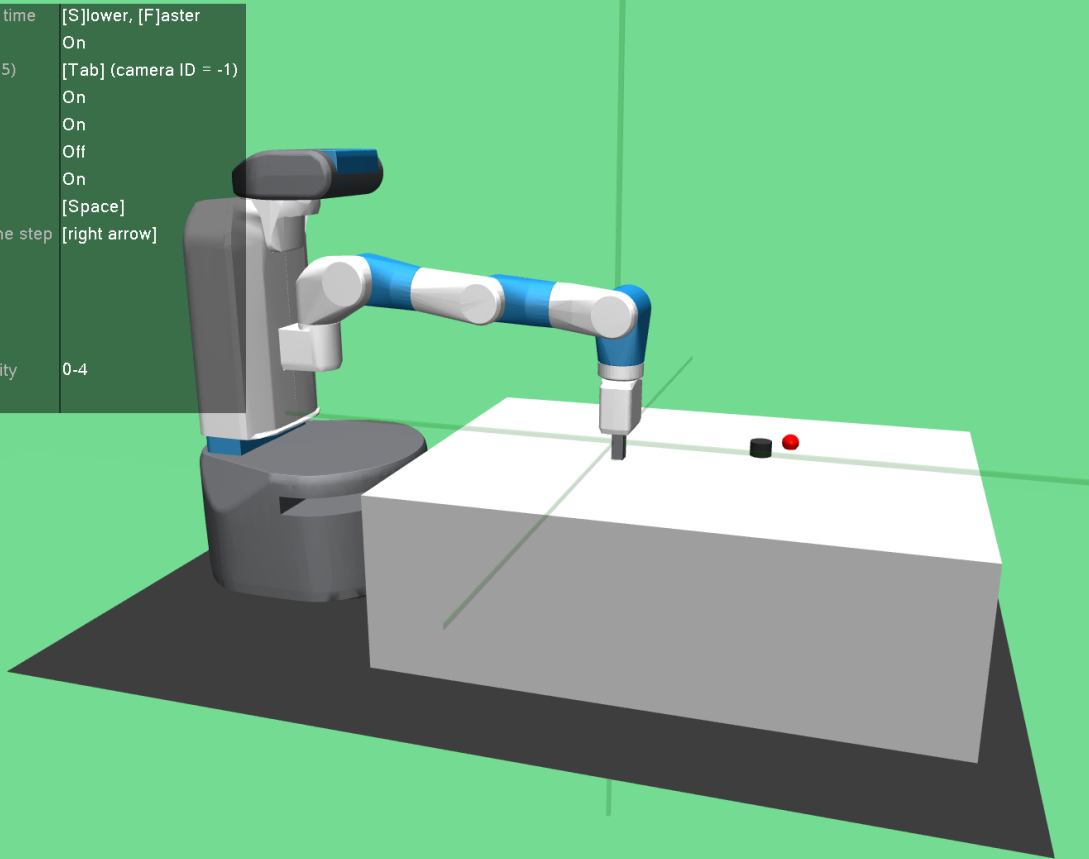




- Run speed = 1.000 x real time
 - Render every frame
 - Switch camera (#cams = 5)
 - Contact forces
 - Reference frames
 - Transparent
 - Display Mujoco bodies
 - Stop
 - Advance simulation by one step
 - Hide Menu
 - Record Video (Off)
 - Capture frame
 - Start .ipdb
 - Toggle geomgroup visibility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



| | |
|-------------------|----|
| FPS | 30 |
| Solver iterations | 2 |

| | |
|------------|---------|
| Step | 860 |
| timestep | 0.00200 |
| n_substeps | 20 |