



- Run speed = 1.000 x real time
 - Render every frame
 - Switch camera (#cams = 5)
 - Contact forces
 - Reference frames
 - Transparent
 - Display Mjocap 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 43
Solver iterations 2

Step 880
timestep 0.00200
n_substeps 20