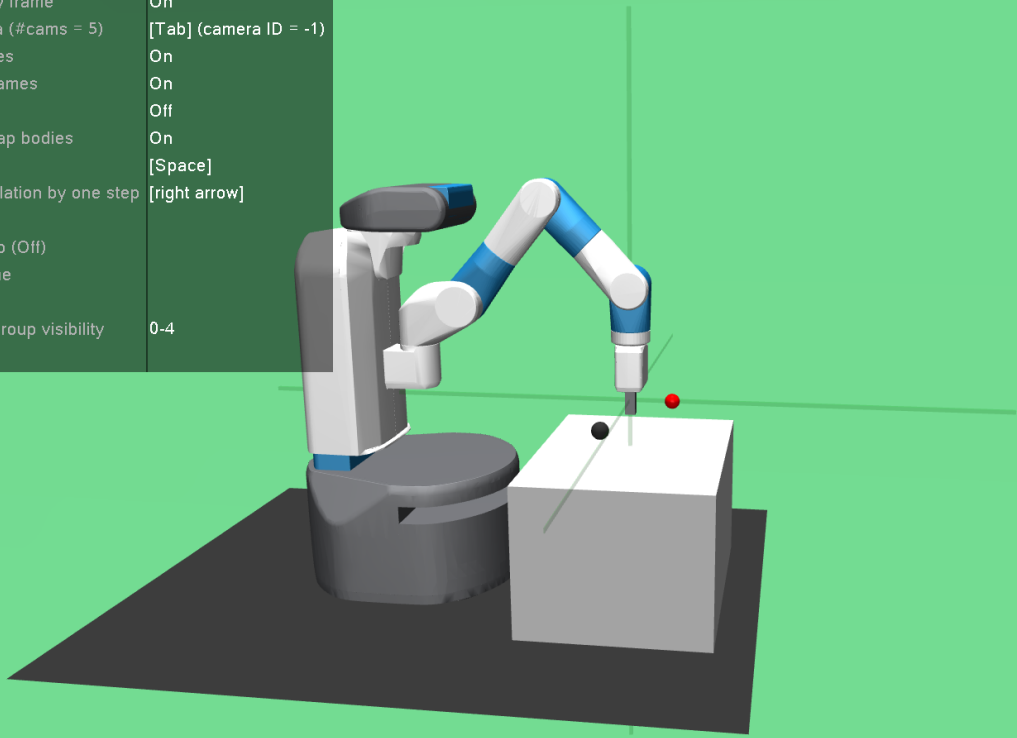




- |                                |                        |
|--------------------------------|------------------------|
| Run speed = 1.000 x real time  | [S]lower, [F]aster     |
| Render every frame             | On                     |
| Switch camera (#cams = 5)      | [Tab] (camera ID = -1) |
| 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	45
Solver iterations	2

Step	460
timestep	0.00200
n_substeps	20