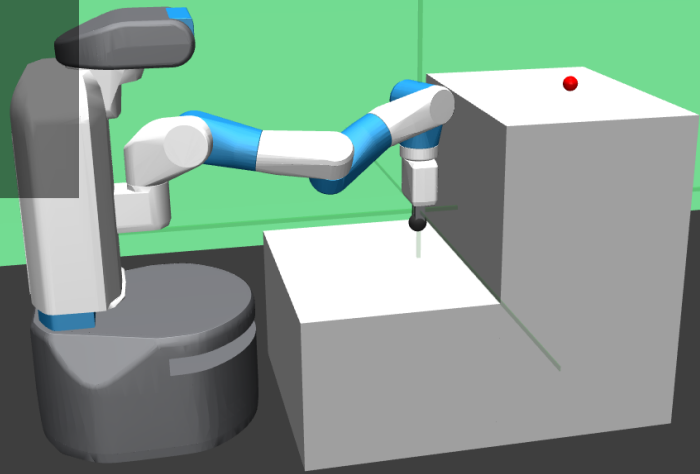




- Run speed = 1.000 x real time
- Render every frame
- Switch camera (#cams = 5)
- Contact forces
- Reference frames
- Transparent
- Display Mujoco bodies
- Stop
- Advance simulation by one step
- Hide Menu
- Record Video (Off)
- Capture frame
- Start ipdb
- Toggle geomgroup visibility

- [S]lower, [F]aster
- On
- [Tab] (camera ID = -1)
- On
- On
- Off
- On
- [Space]
- [right arrow]
- 0-4



FPS 42
 Solver iterations 2

Step 960
 timestep 0.00200
 n_substeps 20