












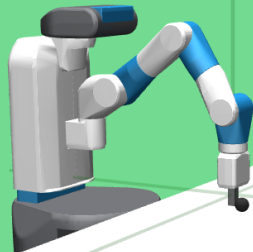
	Run speed = 1.000 x real time	[S]lower, [F]aster
	Render every frame	On
	Switch camera (#cams = 5)	[Tab] (camera ID = -1)
	Contact forces	On
	Reference frames	On
	Transparent	Off
	Display Mujoco bodies	On
	Stop	[Space]
	Advance simulation by one step	[right arrow]
	Hide Menu	
	Record Video (Off)	
	Capture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



FPS	28
Solver iterations	2

Step	620
timestep	0.00200
n_substeps	20