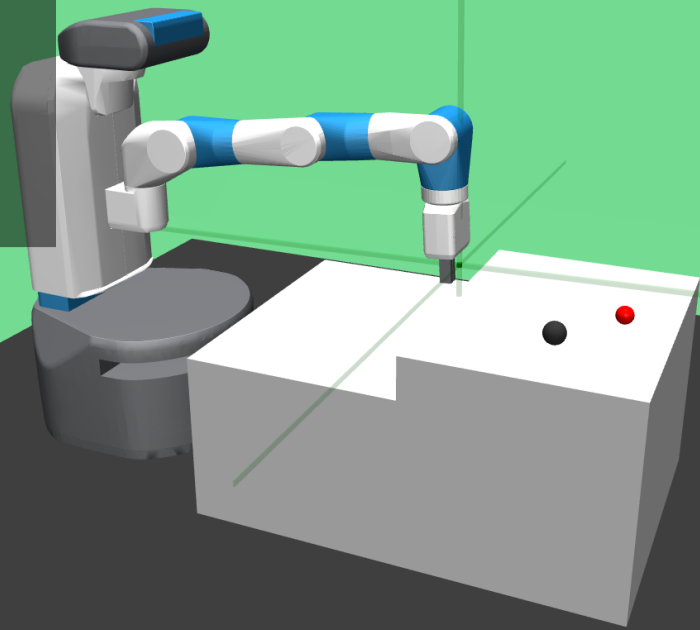




- Run speed = 1.000 x real time
- Ren[d]er every frame
- Switch camera (#cams = 5)
- [C]ontact forces
- Referenc[e] frames
- T[r]ansparent
- Display [M]ocap bodies
- Stop
- Advance simulation by one step
- [H]ide Menu
- Record [V]ideo (Off)
- Cap[t]ure frame
- Start [i]pdb
- Toggle geomgroup visibility

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



FPS	41
Solver iterations	3

Step	800
timestep	0.00200
n_substeps	20