

Real time robot view

Joint positions: Coord. positions:

J1: __

X: __

J2: __

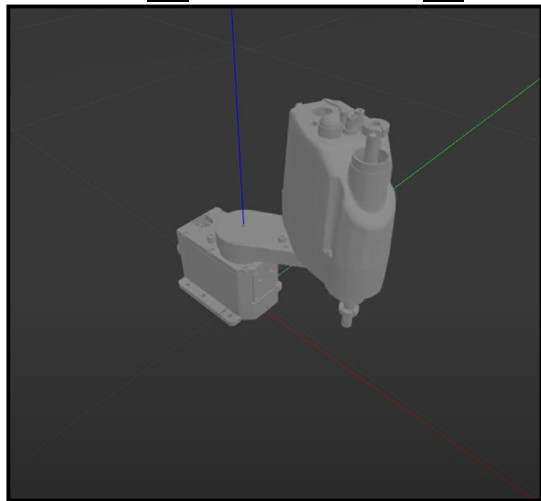
Y: __

J3: __

Z: __

J4: __

R: __



Data

◁ Object detection view ▷

