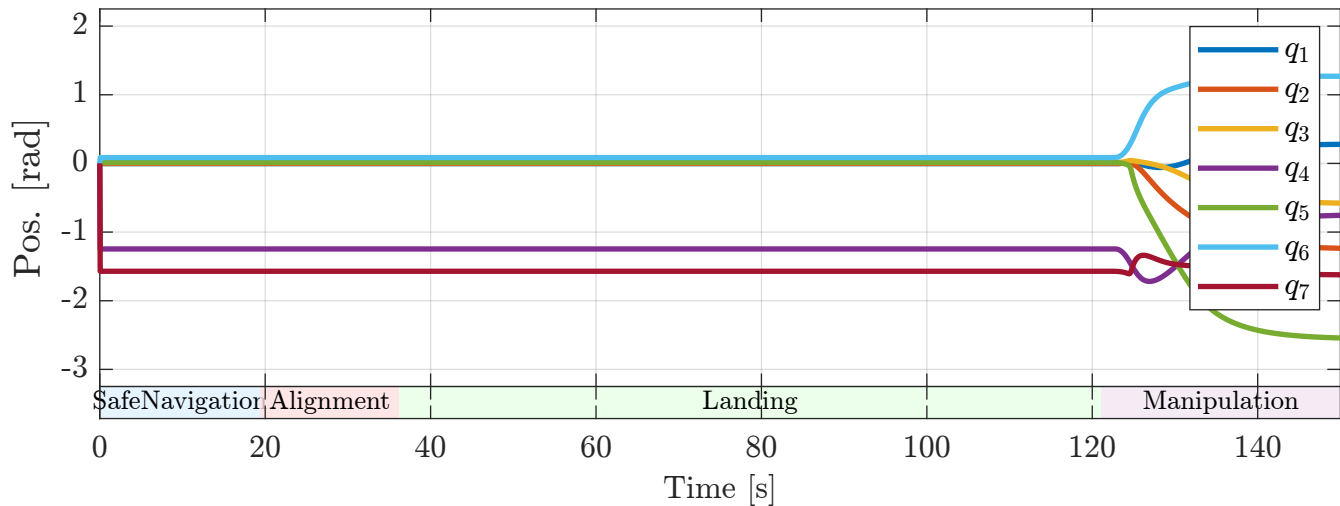


Manipulator - Joint Positions (q)



Manipulator - Joint Velocities (\dot{q})

