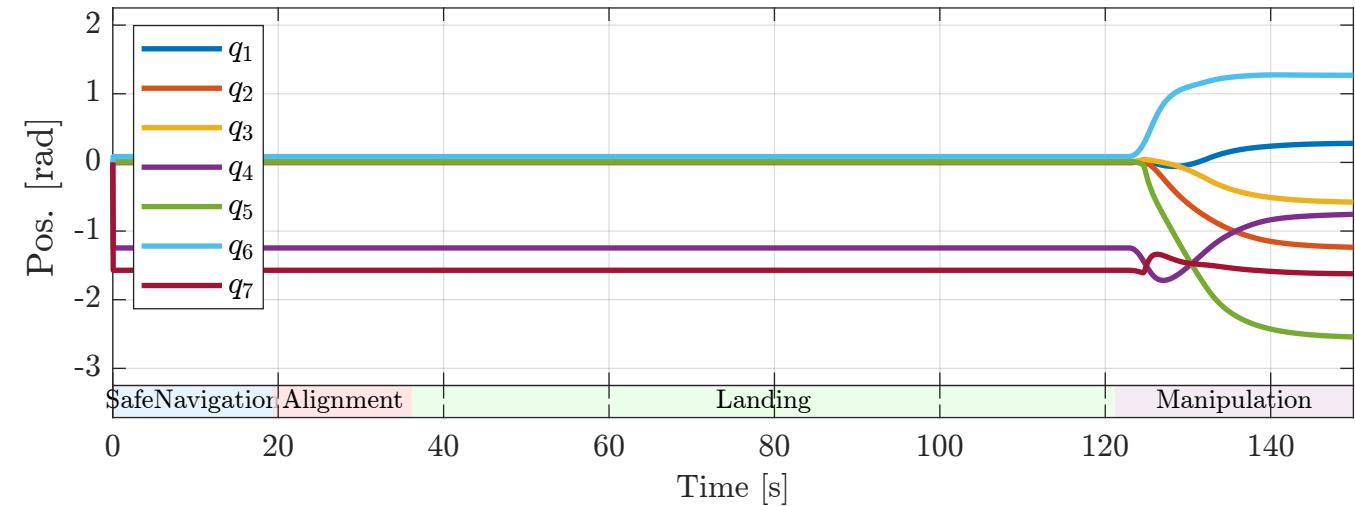


# Manipulator - Joint Positions ( $q$ )



# Manipulator - Joint Velocities ( $\dot{q}$ )

