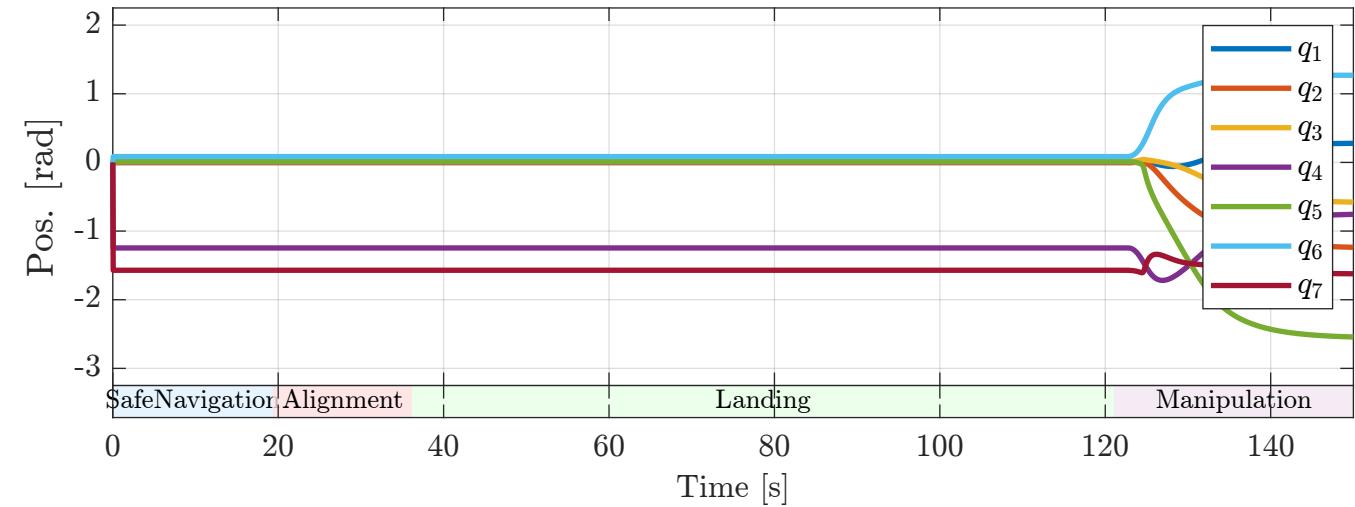


## Manipulator - Joint Positions ( $q$ )



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

