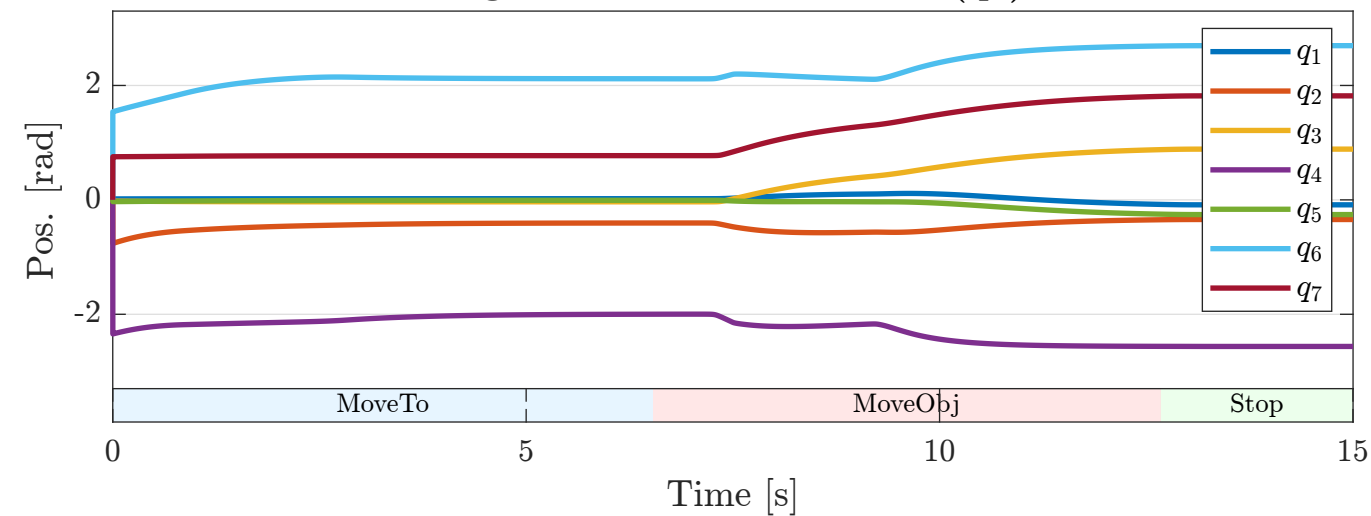


# Right Arm - Joint Positions ( $q_R$ )



# Right Arm - Joint Velocities ( $\dot{q}_R$ )

