Optimal Joint Motion

Joint Trajectories — $\mathbf{q}$ [rad] vs t [s]

Legend: q_1, q_2, q_3, q_4, q_5, q_6
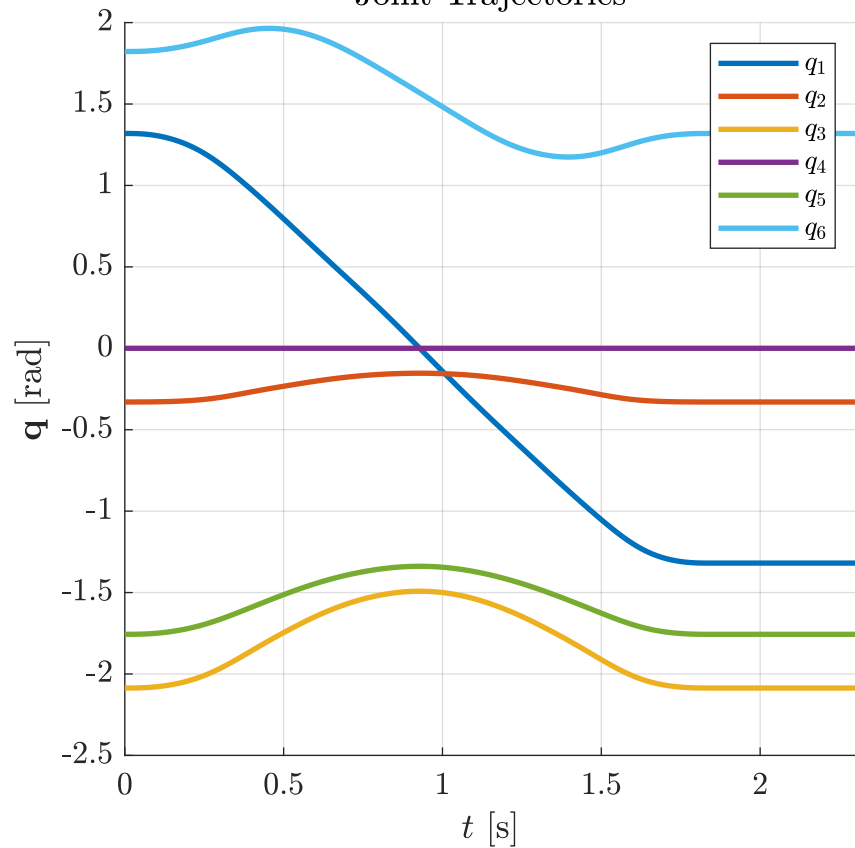
Normalized Joint Velocities — $|\dot{\mathbf{q}}/\dot{\mathbf{q}}_{\max}|$ [-] vs t [s]

Legend: $\dot{q}_1$, $\dot{q}_2$, $\dot{q}_3$, $\dot{q}_4$, $\dot{q}_5$, $\dot{q}_6$