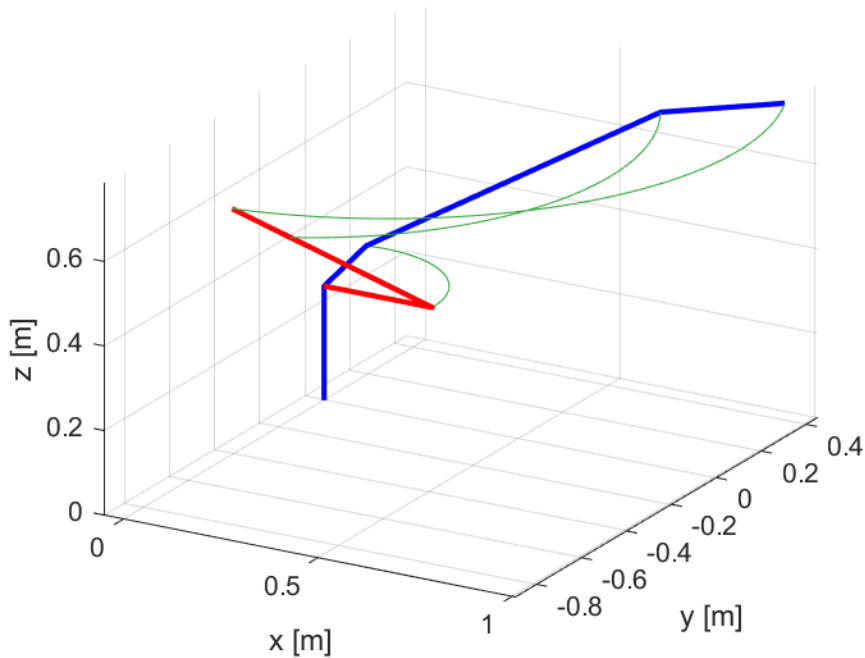


Manipulator poses and joint trajectory



— P1 pose — P2 pose — joint trajectory