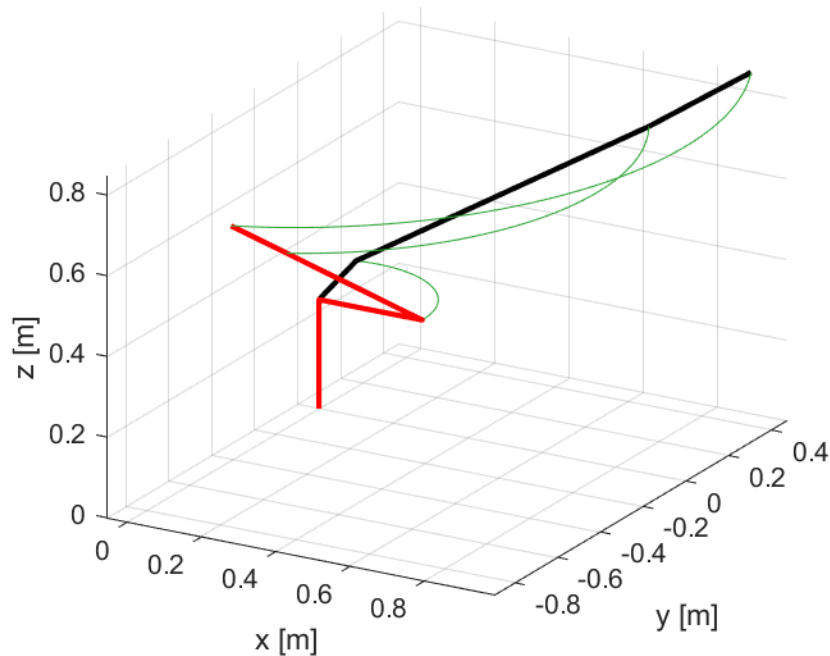


## Manipulator poses and joint trajectory



— P3 pose — P1 pose — joint trajectory