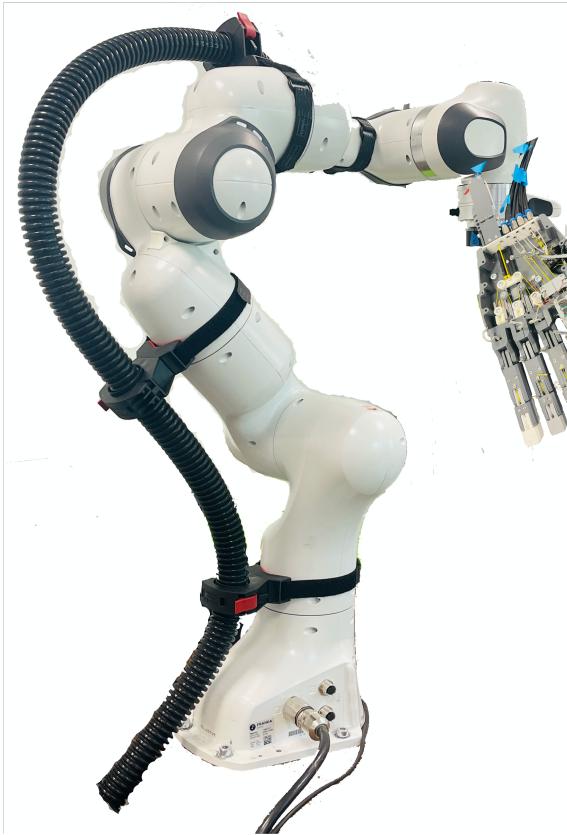


**Given: Joint pose**

**Find: Joint angle**



**Optimize 11 objective:**

Position matching

Orientation matching

Smoothness motion

Continuous motion

Kinematic singularity avoidance

Joint torque limits

Small change of 5th, 6th joint angles

7th joint angle compensation

7th joint angle velocity minimum

Jerk smoothness

Minimum bending of cable