Joint Angles θ (Cubic Polynomial, T=2.0s)
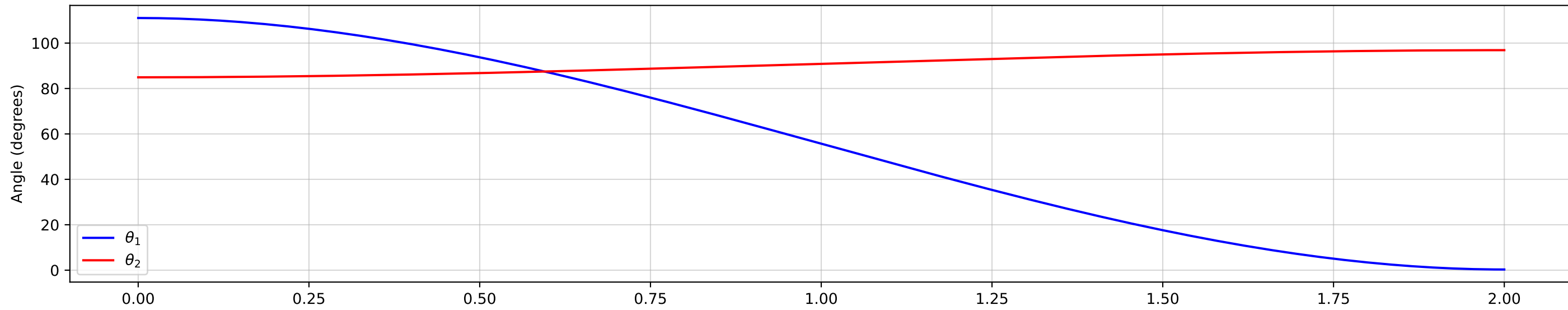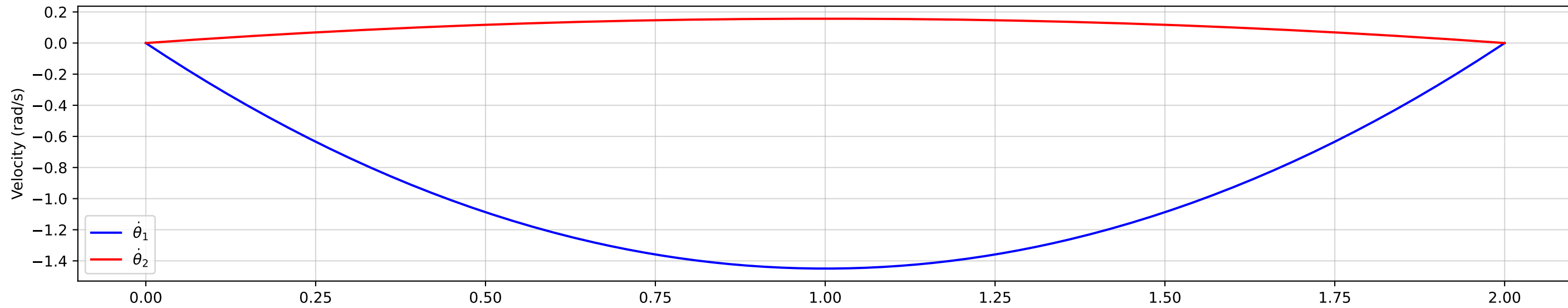
Joint Angular Velocities $\dot{\theta}$

Required Joint Torques τ (Calculated by Dynamics)