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"O T EE": [0.998578,0.0328747,-0.0417381,0,0.0335224,-0.999317,0.0149157,0,-0.04122,-0.016294,
           -0.999017.0.0.305468.-0.00814133.0.483198.1].
"O T EE d": [0.998582,0.0329548,-0.041575,0,0.0336027,-0.999313,0.0149824,0,-0.0410535,
             -0.0163585, -0.999023, 0, 0.305444, -0.00810967, 0.483251, 1],
"F T EE": [0.7071,-0.7071,0,0,0.7071,0.7071,0,0,0,0,1,0,0,0,0.1034,1],
"EE T K": [1,0,0,0,0,1,0,0,0,0,1,0,0,0,0,1],
"m ee": 0.73, "F x Cee": [-0.01,0,0.03], "I ee": [0.001,0,0,0,0.0025,0,0,0.0017],
"m load": 0, "F x Cload": [0,0,0], "I load": [0,0,0,0,0,0,0,0,0],
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"elbow": [-0.0207622,-1], "elbow d": [-0.0206678,-1],
"tau J": [-0.00359774,-5.08582,0.105732,21.8135,0.63253,2.18121,-0.0481953],
"tau J d": [0,0,0,0,0,0,0,0],
"dtau J": [-54.0161,-18.9808,-64.6899,-64.2609,14.1561,28.5654,-11.1858],
"q": [0.0167305,-0.762614,-0.0207622,-2.34352,-0.0305686,1.53975,0.753872],
"dq": [0.00785939,0.00189343,0.00932415,0.0135431,-0.00220327,-0.00492024,0.00213604],
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"tau ext hat filtered": [0.00187271,-0.700316,0.386035,0.0914781,-0.117258,-0.00667777,
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"O F ext hat K": [-2.06065,0.45889,-0.150951,-0.482791,-1.39347,0.109695],
"K F ext hat K": [-2.03638,-0.529916,0.228266,-0.275938,0.434583,0.0317351],
"theta": [0.01673,-0.763341,-0.0207471,-2.34041,-0.0304783,1.54006,0.753865],
"dtheta": [0,0,0,0,0,0,0,0],
"current errors": [], "last motion errors": [],
"control command success rate": 0, "robot mode": "Idle", "time": 3781435
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