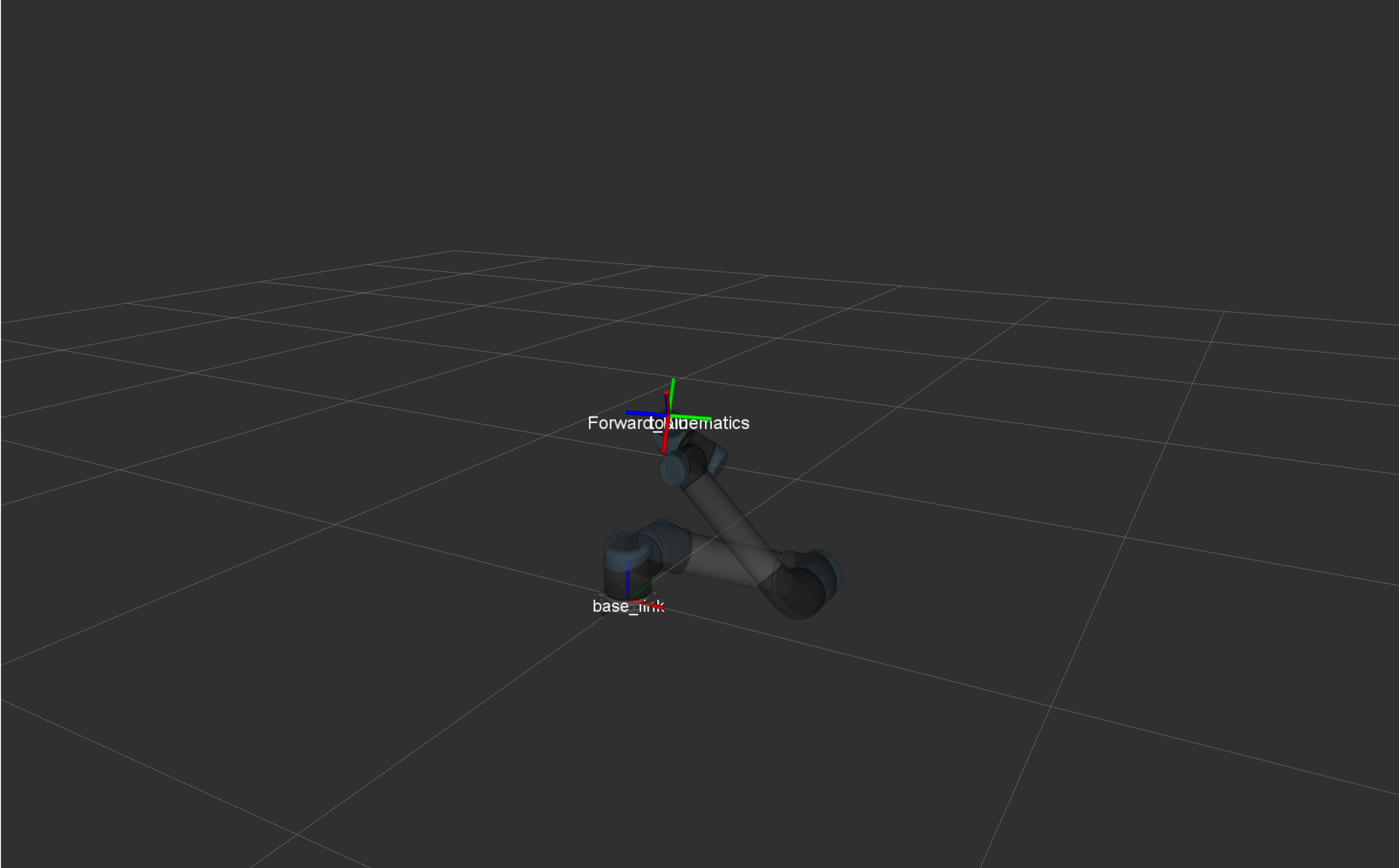
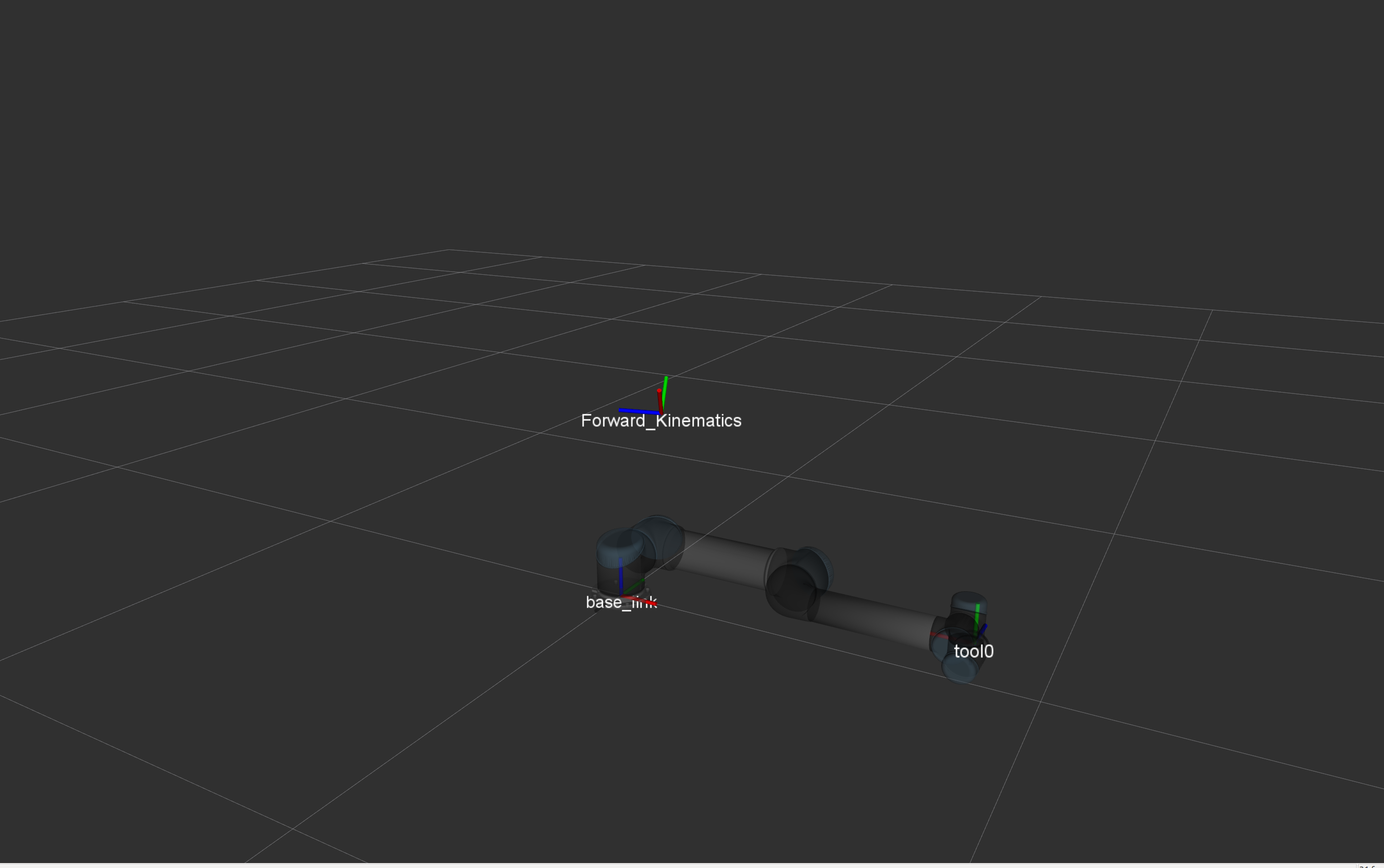
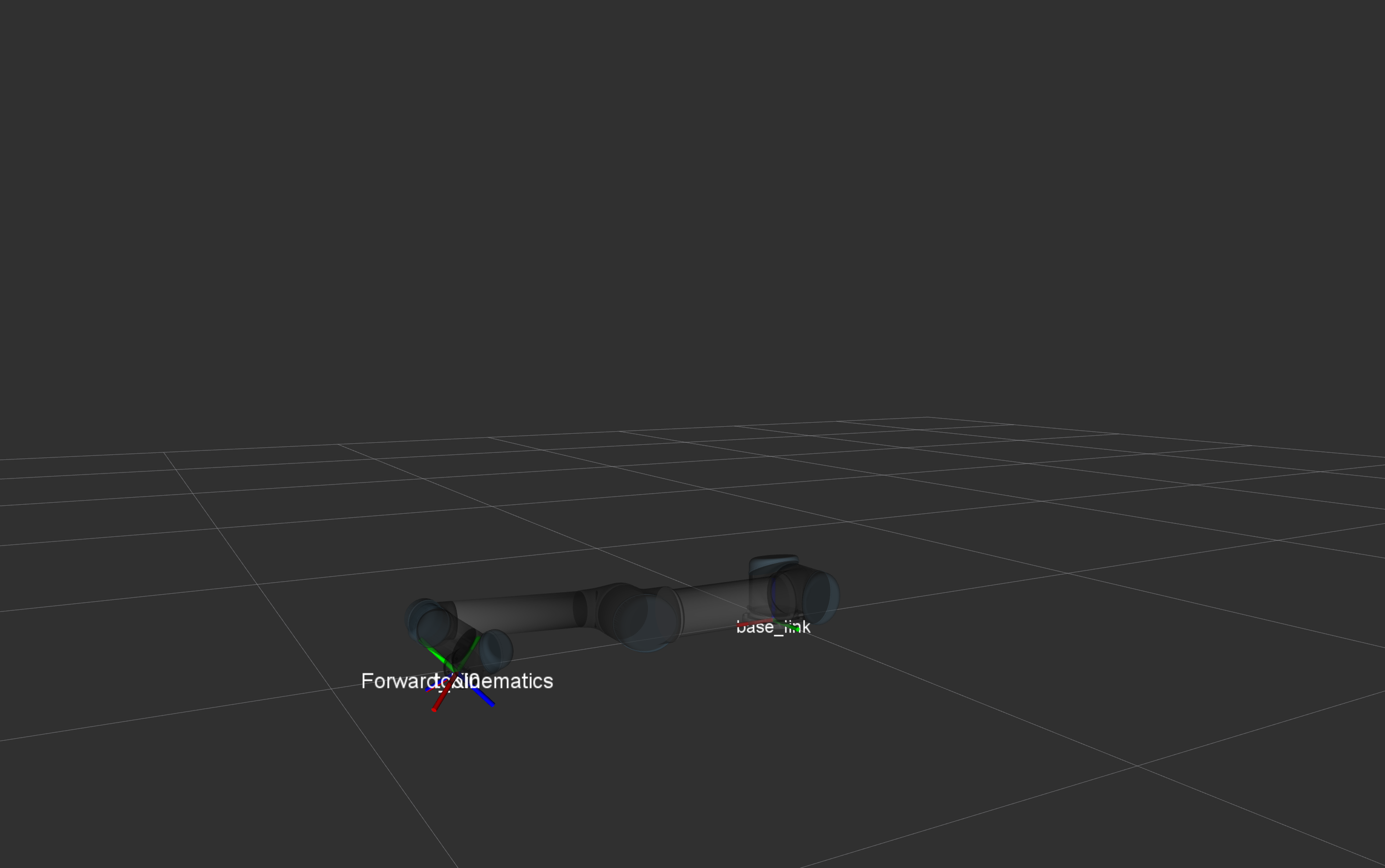
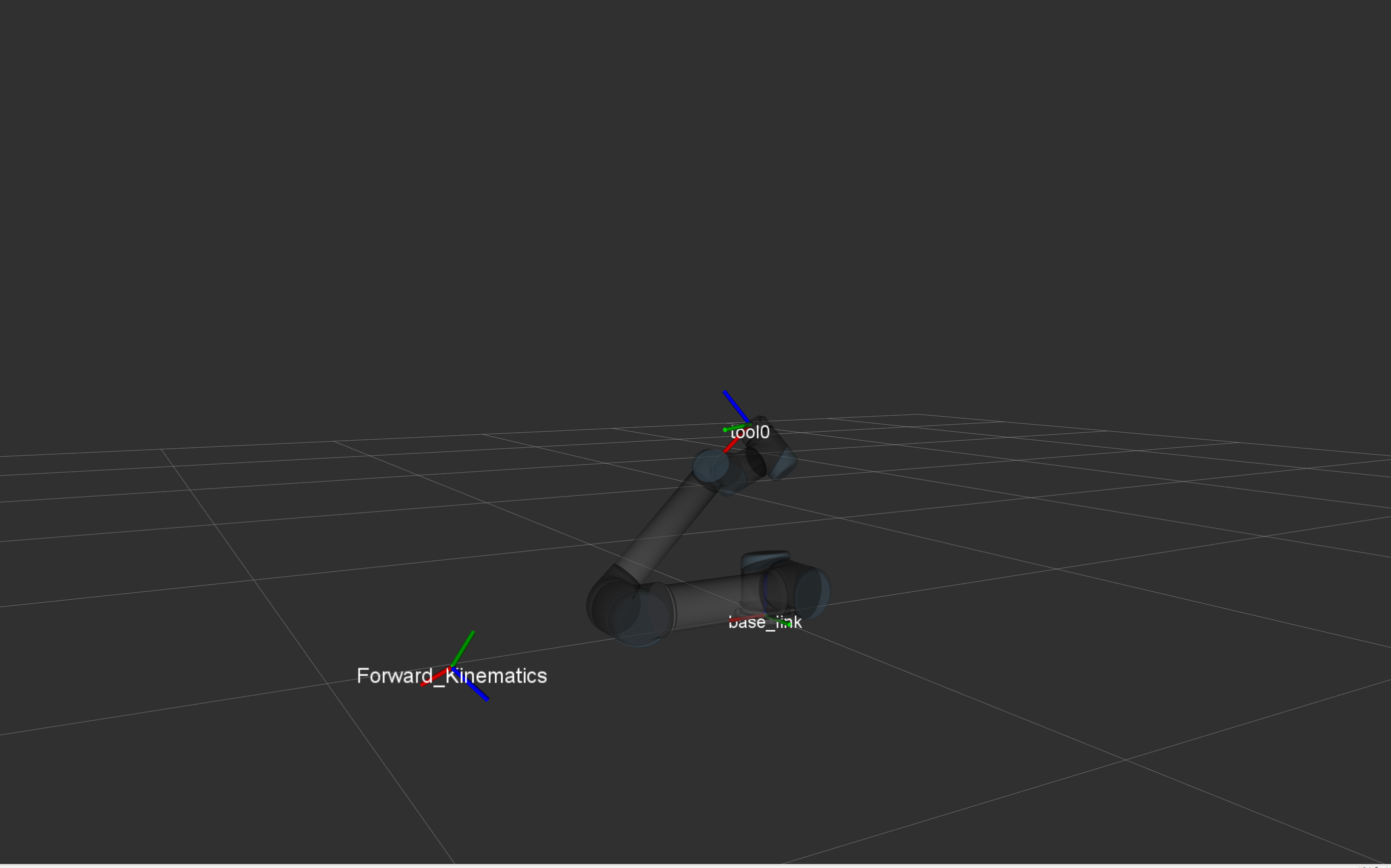
Forward Kinematics Screen Shots

A random joint configuration is generated. The rigid transform g is computed according to the forward map. These images show a frame placed g relative to the base frame, and then ur5 set to the original joints (and how it lines up with the placed frame).

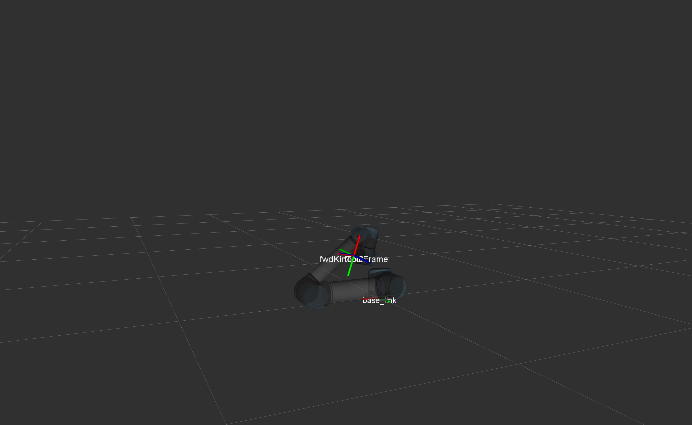
**Transform 1**

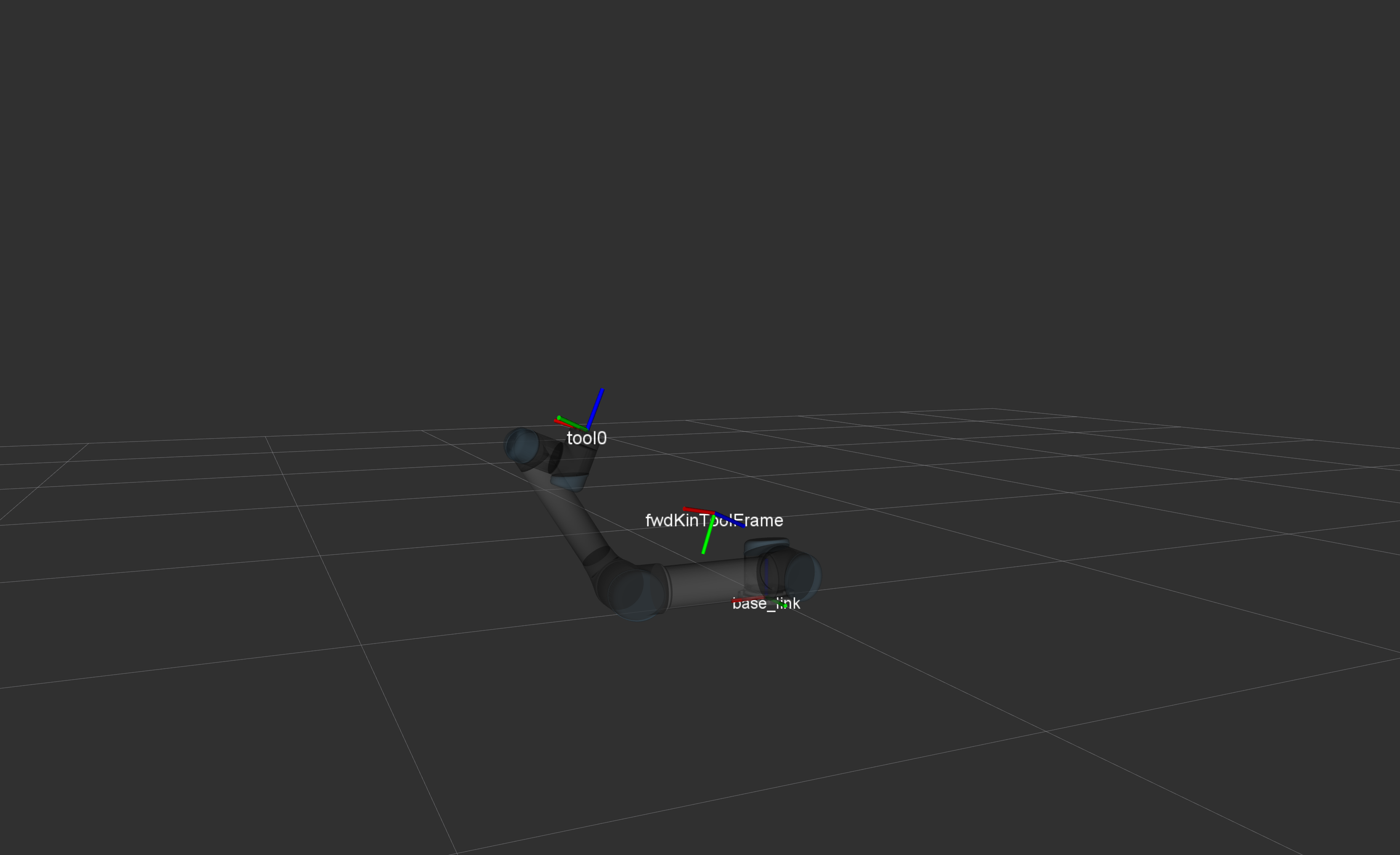


**Transform 2**

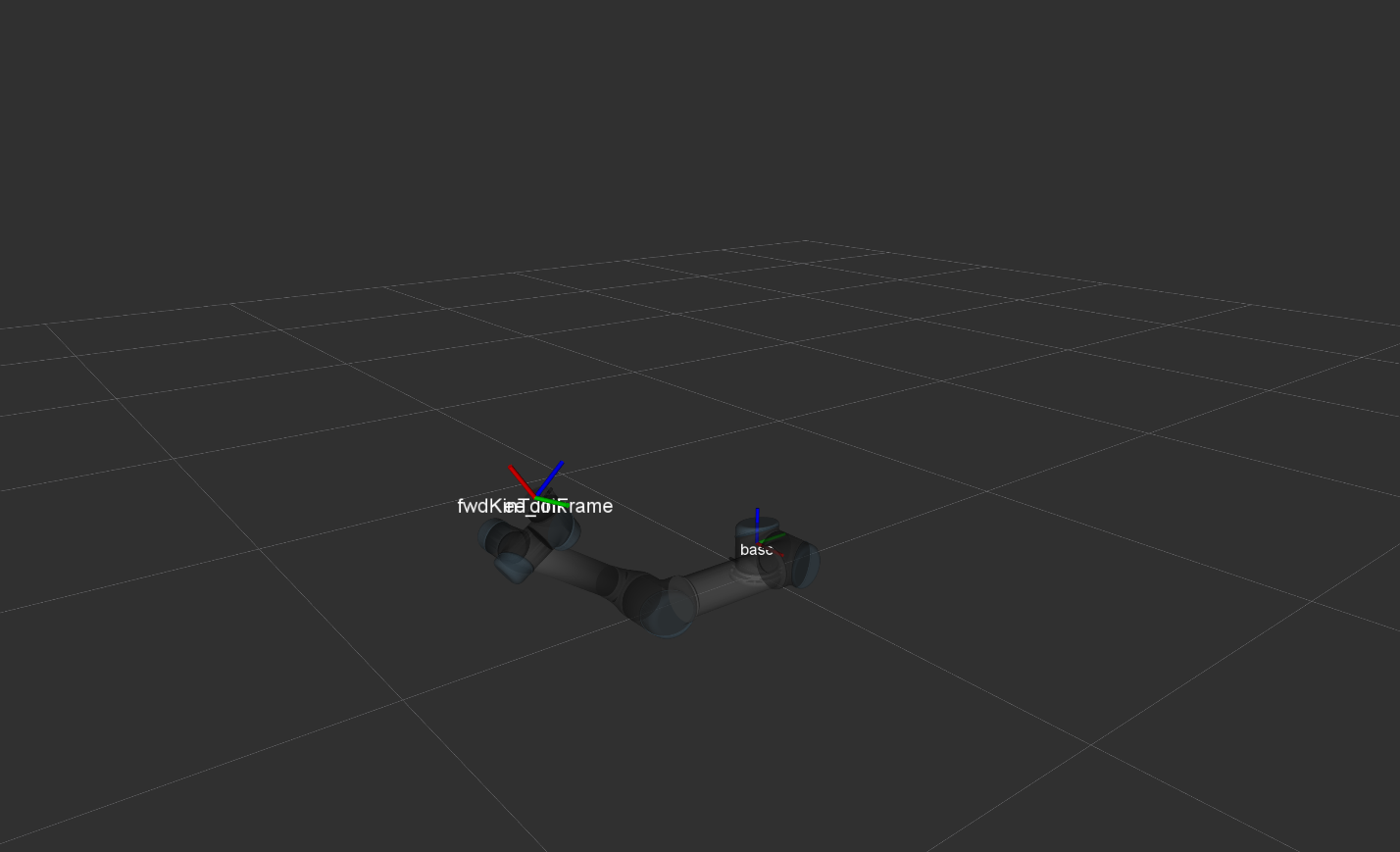


**Transform 3**

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**Transform 4**

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