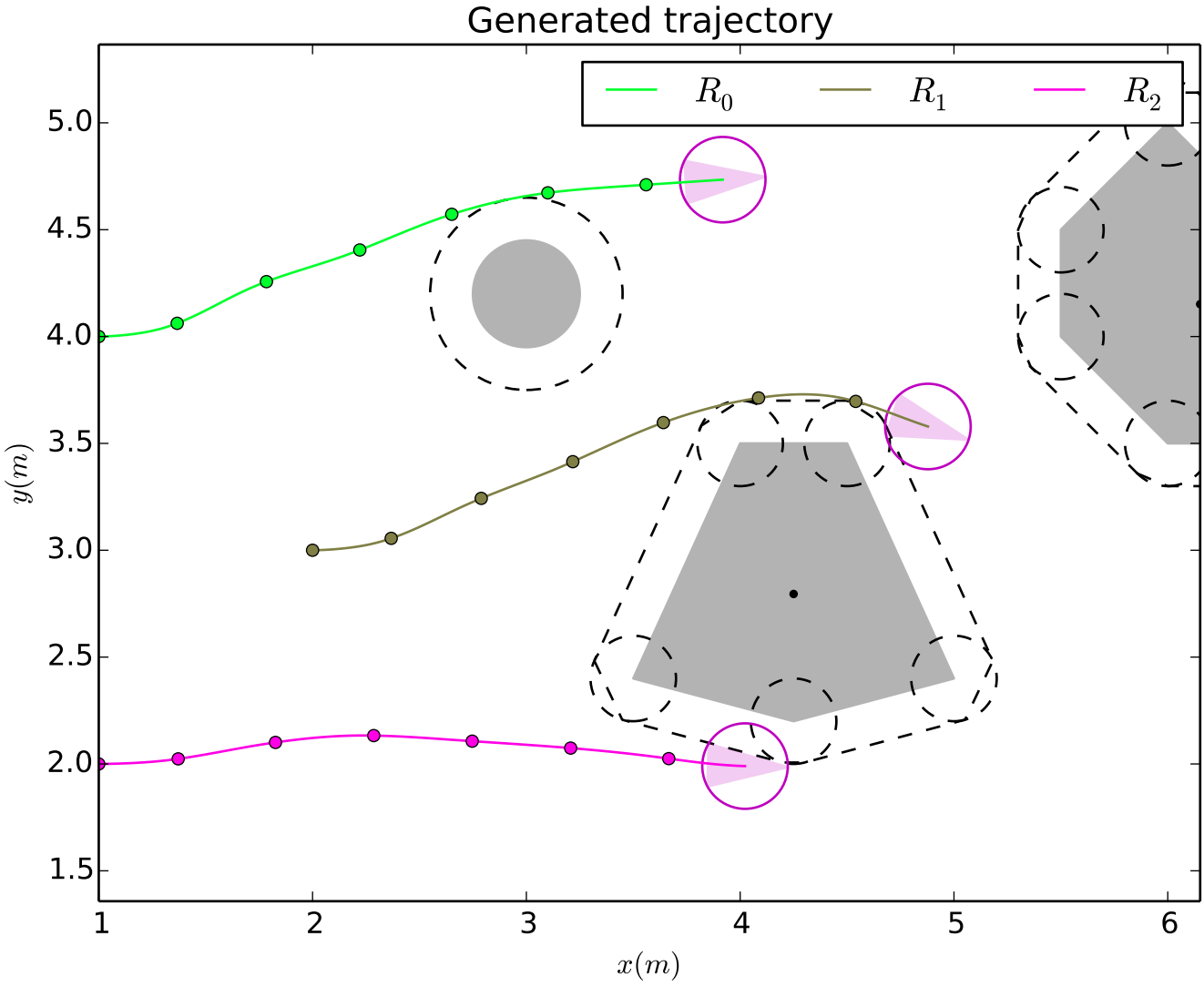
Generated trajectory
R_0
R_1
R_2
5.0
4.5
4.0
3.5
3.0
2.5
2.0
1.5
$y(m)$
1
2
3
4
5
6
$x(m)$