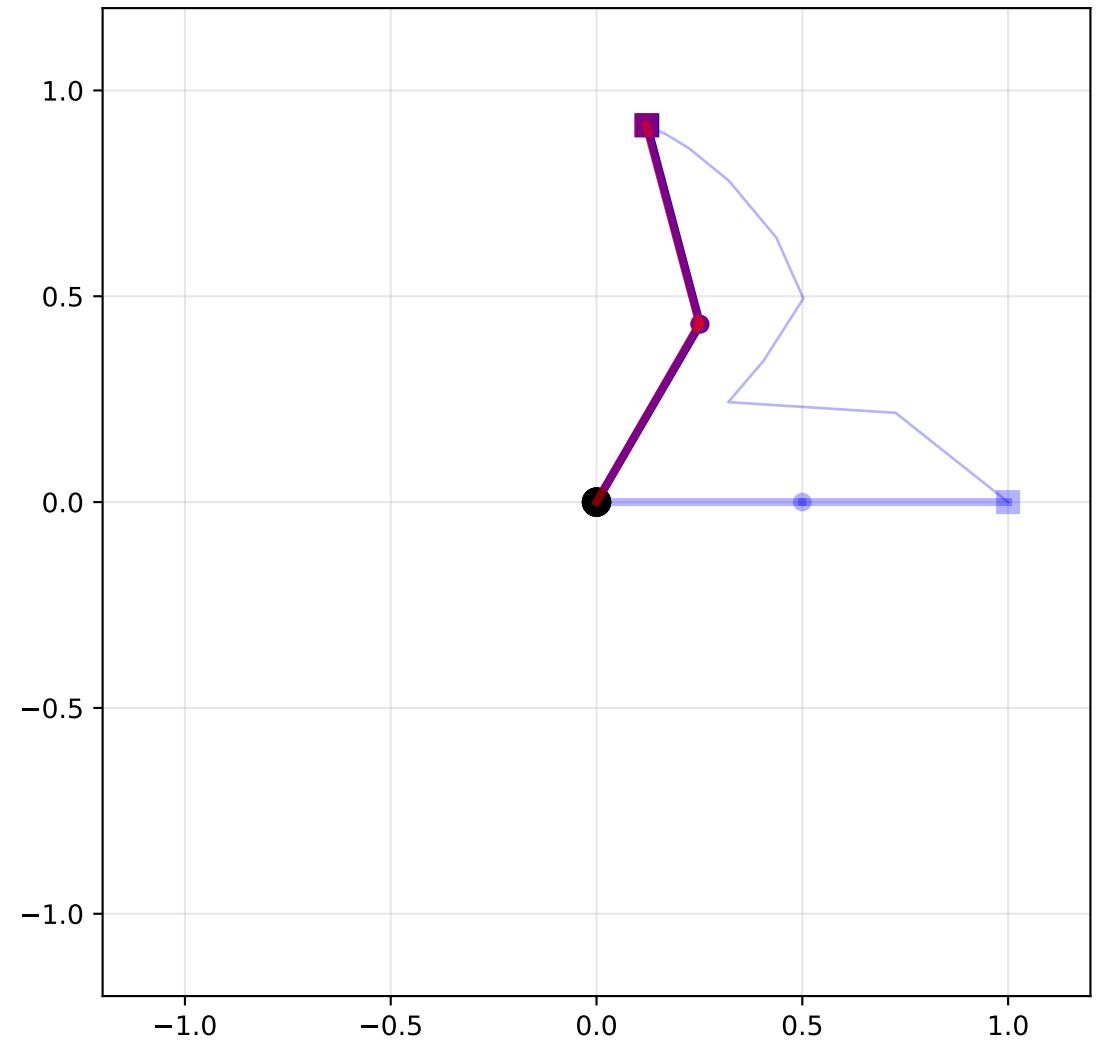
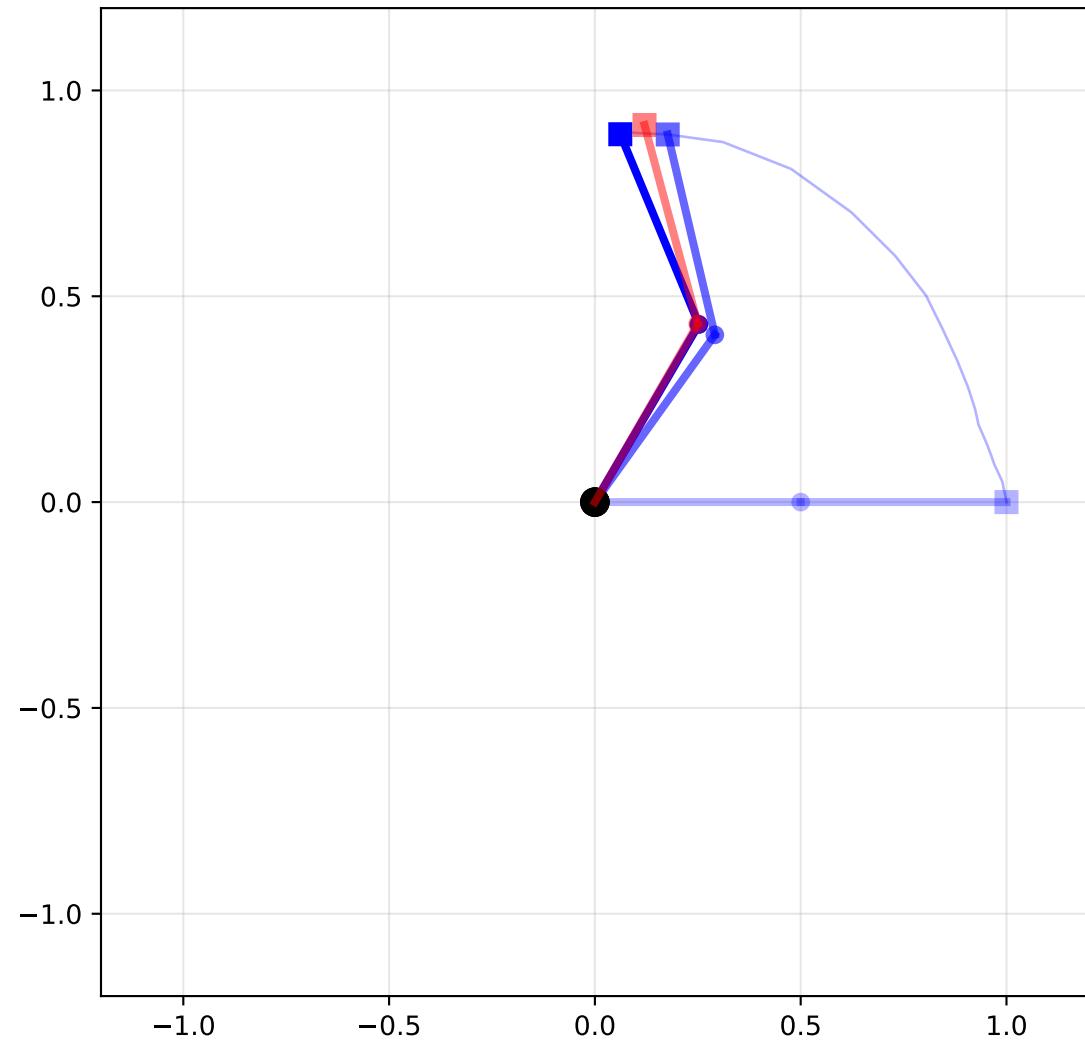


# Manipulator Motion Sequences

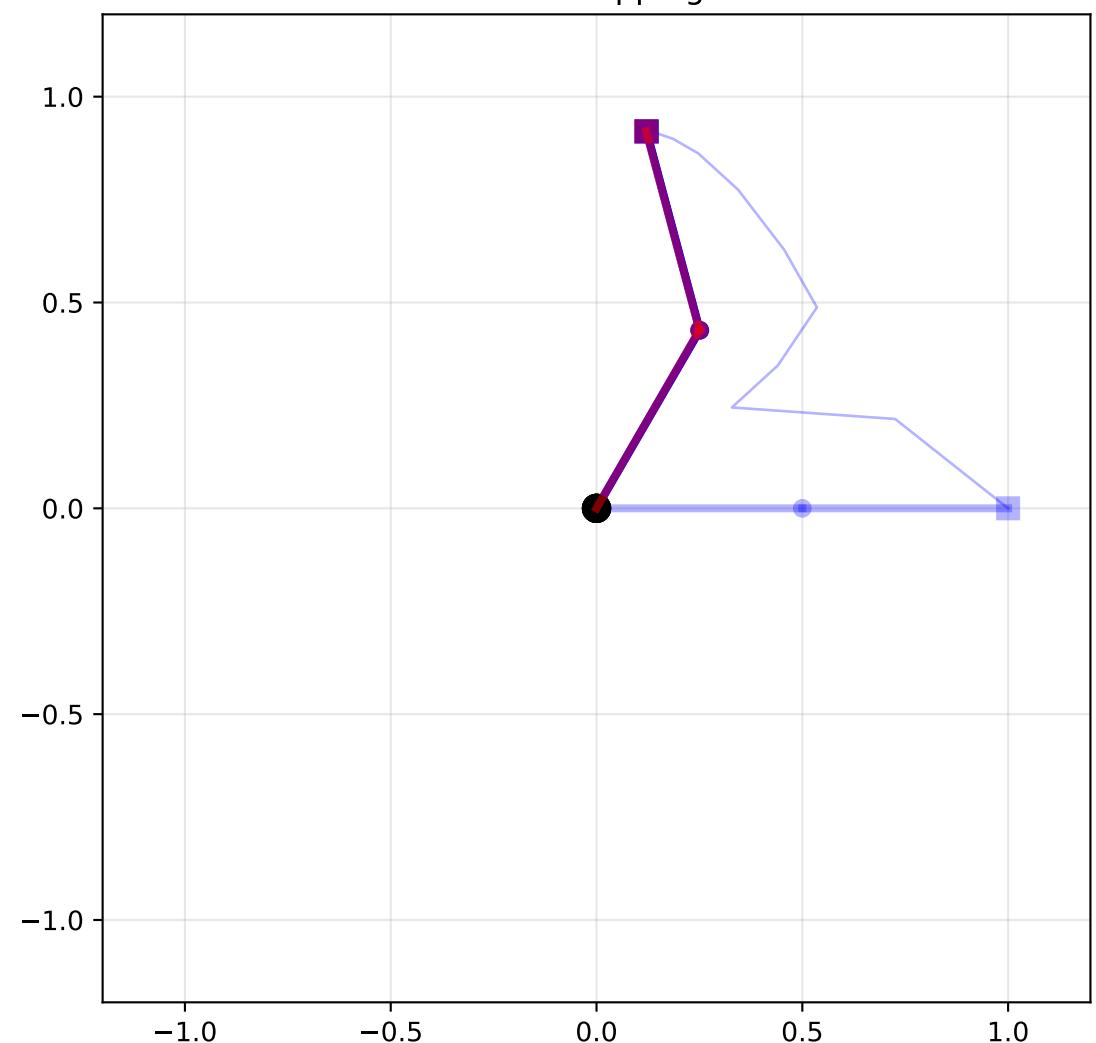
Computed Torque



PD+Gravity



Backstepping



LQR

