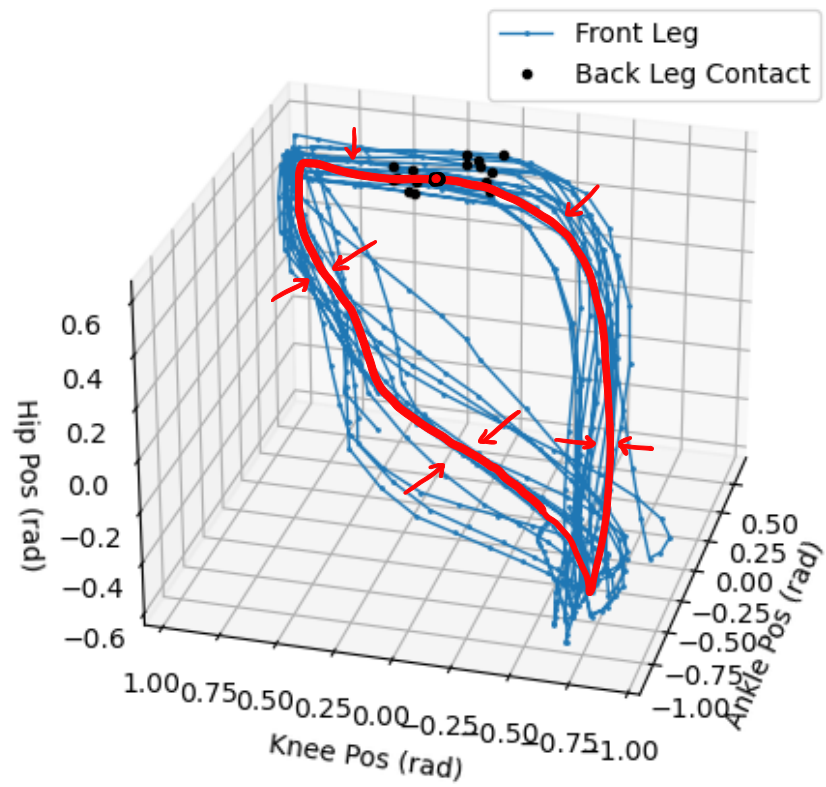
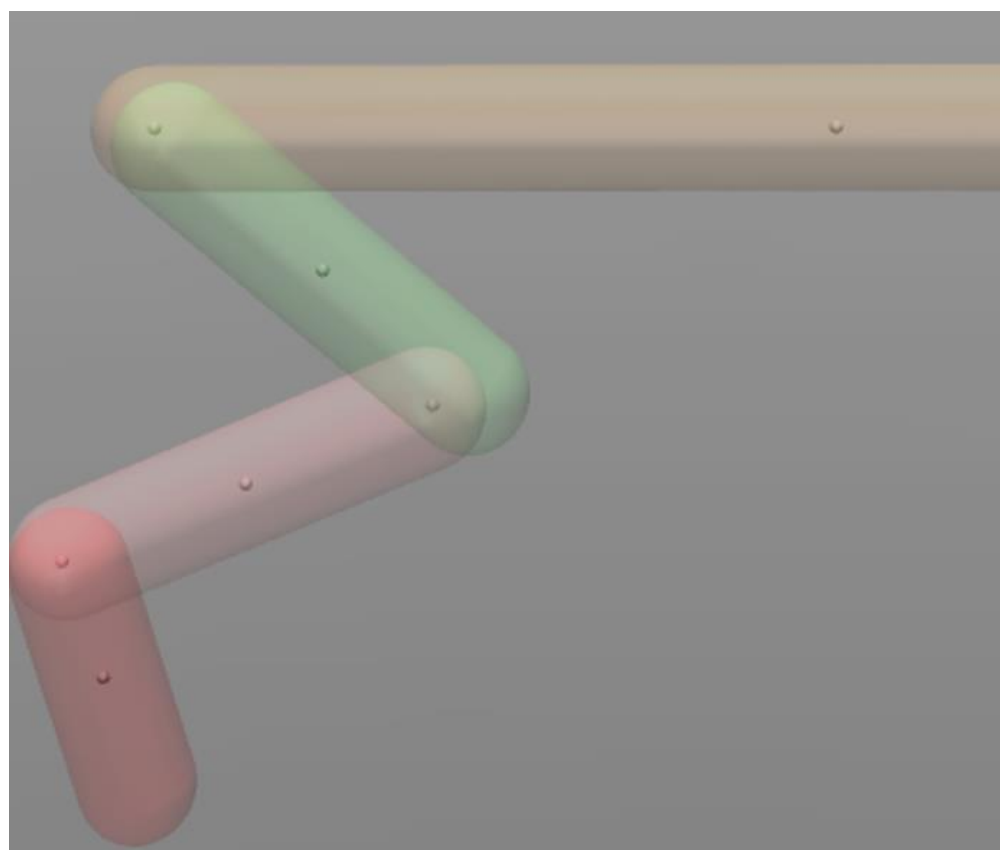
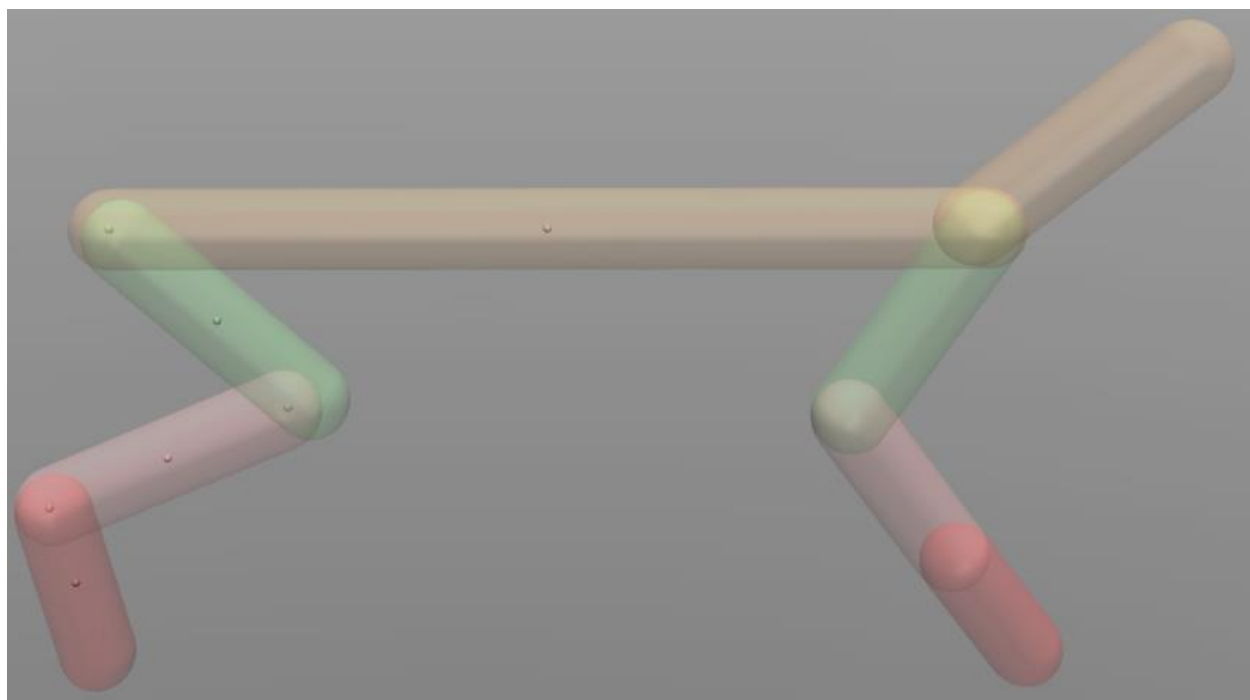
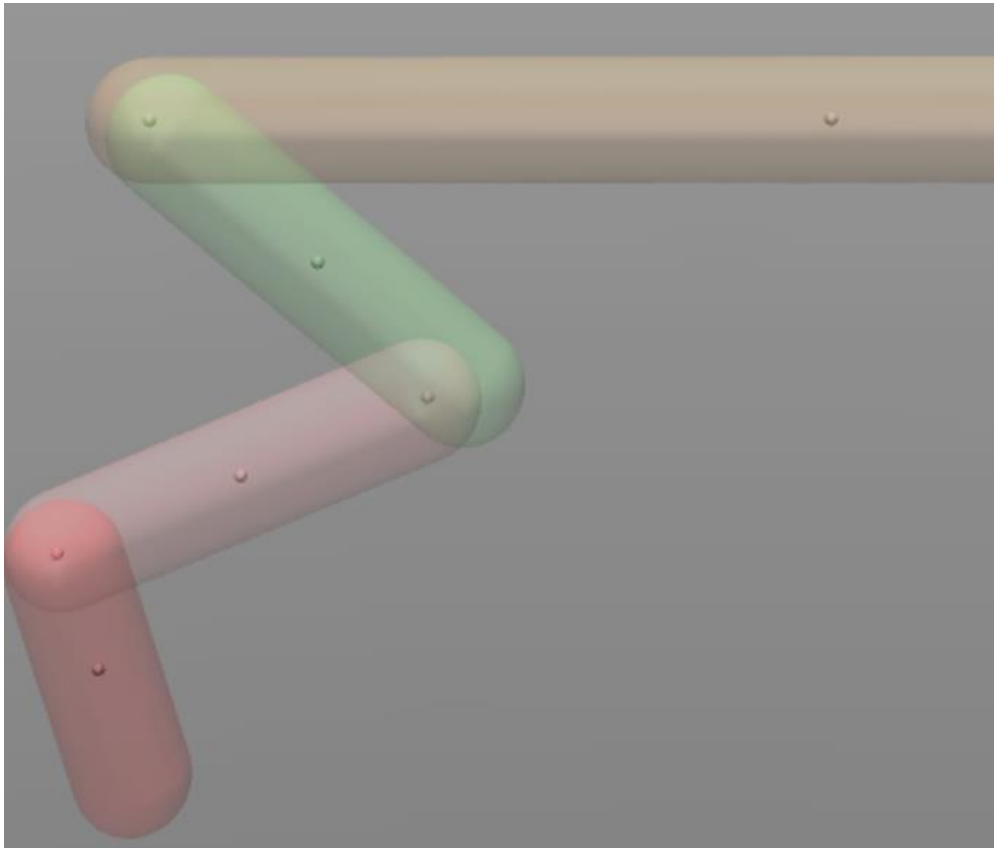


Leg Joint Position







```
<!-- # Cheetah Robot Construction-->
<worldbody>
<light cutoff="100" diffuse="1 1 1" dir="-0 0 -1.3" directional="true" exponent="1" pos="0 0 1.3" specular=".1 .1 .1"/>
<geom conaffinity="1" condim="3" material="MatPlane" name="floor" pos="0 0 0" rgba="1 1 1 1" size="4 4 4" type="plane"/>

<!-- TORSE/HEAD -->
<body name="torso" pos="0 0 0.7">
  <camera name="track" mode="trackcom" pos="0 -3 0.3" xyaxes="1 0 0 0 1"/>
  <!-- # Constrains Cheetah to 2D x-z plane, with rotation/hinge about y-axis into page using 'fake' joint constraints -->
  <joint armature="0" axis="1 0 0" damping="0" limited="false" name="rootx" pos="0 0 0" stiffness="0" type="slide"/>
  <joint armature="0" axis="0 0 1" damping="0" limited="false" name="rootz" pos="0 0 0" stiffness="0" type="slide"/>
  <joint armature="0" axis="0 1 0" damping="0" limited="false" name="rooty" pos="0 0 0" stiffness="0" type="hinge"/>
  <geom fromto="-0.5 0 0 .5 0 0" name="torso" size="0.046" type="capsule"/>
  <geom axisangle="0 1 0 .87" name="head" pos=".6 0 .1" size="0.046 .15" type="capsule"/>
  <!-- # BACK -->
  <site name='torso_geom_com' pos='0 0 0'/>
  <site name='bt_body_frame' pos='-.5 0 0'/>
  <body name="bthigh" pos="-.5 0 0">
    <joint axis="0 1 0" damping="6" name="bthigh" pos="0 0 0" range="-.52 1.05" stiffness="240" type="hinge"/>
    <geom axisangle="0 1 0 -3.8" name="bthigh" pos=".1 0 -.13" rgba="0.505 0.815 0.501 1" size="0.046 .145" type="capsule"/>
    <site name='bt_geom_com' pos='.1 0 -.13'/>
    <site name='bs_body_frame' pos='.16 0 -.25'/>
    <body name="bshin" pos="-.16 0 -.25">
      <joint axis="0 1 0" damping="4.5" name="bshin" pos="0 0 0" range="-.785 .785" stiffness="180" type="hinge"/>
      <geom axisangle="0 1 0 -2.03" name="bshin" pos="-.14 0 -.07" rgba="0.9 0.6 0.6 1" size="0.046 .15" type="capsule"/>
      <site name='bs_geom_com' pos='-.14 0 -.07'/>
      <site name='bf_body_frame' pos='-.28 0 -.14'/>
      <body name="bfoot" pos="-.28 0 -.14">
        <joint axis="0 1 0" damping="3" name="bfoot" pos="0 0 0" range="-.4 .785" stiffness="120" type="hinge"/>
        <geom axisangle="0 1 0 -.27" name="bfoot" pos=".03 0 -.097" rgba="0.882 0.215 0.215 1" size="0.046 .094" type="capsule"/>
        <site name='bf_geom_com' pos='.03 0 -.097'/>
      </body>
    </body>
  </body>
</body>
</body>
```