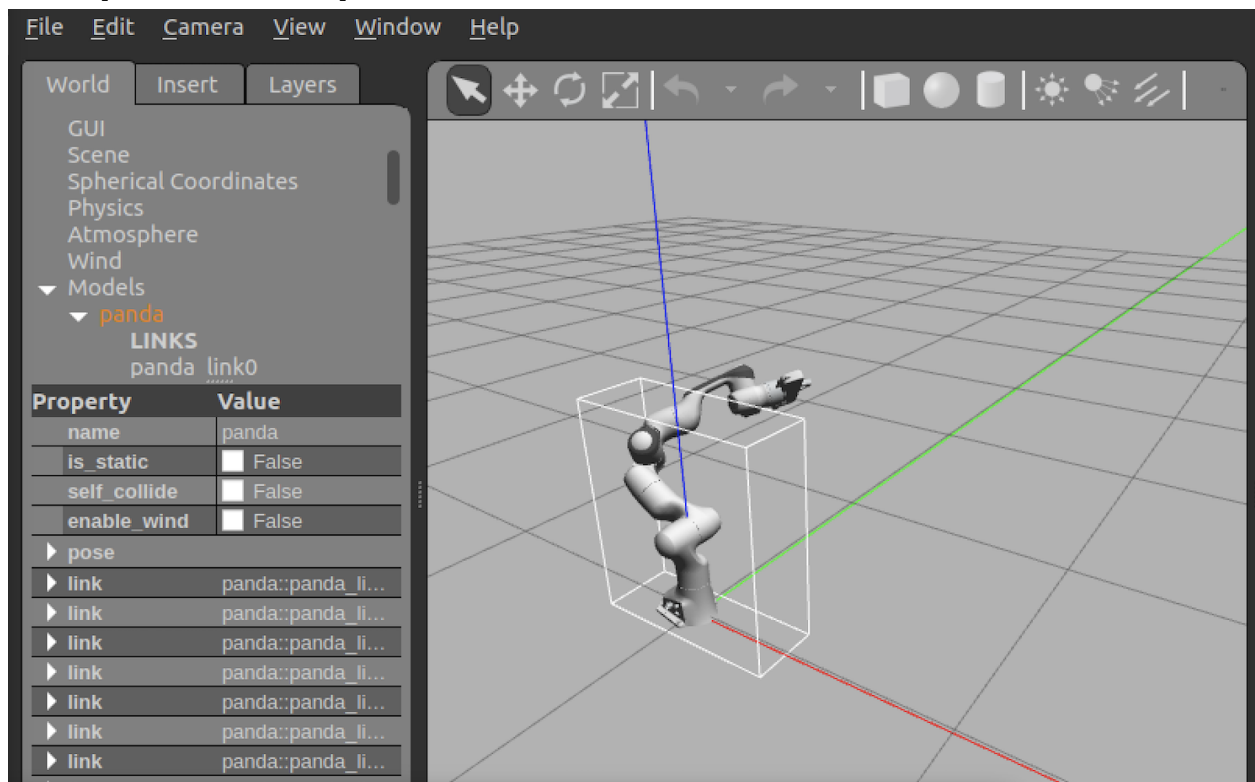


The screenshot shows the ROS2 GUI interface. On the left, the 'World' tab is active, displaying a tree view of the environment. Under 'Models', the 'panda' model is selected. Below the tree, a 'Property Value' table is shown:

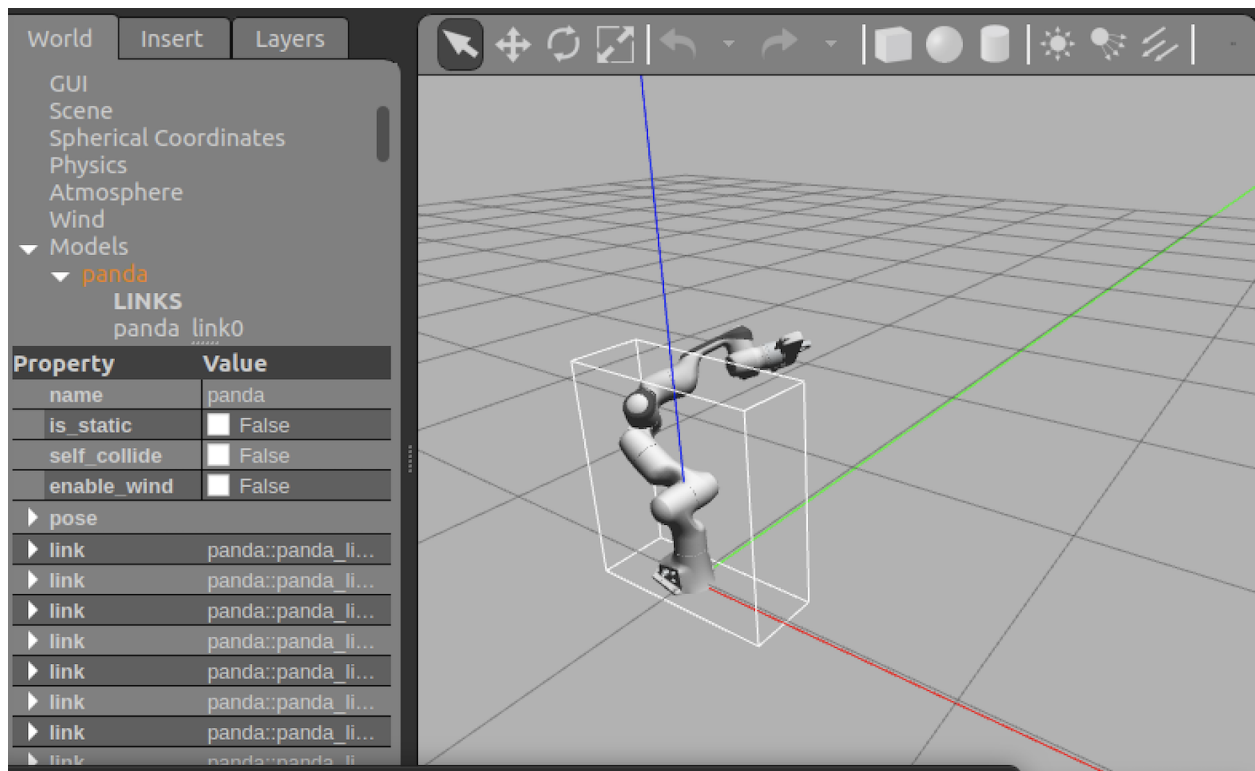
Property	Value
name	panda
is_static	<input type="checkbox"/> False
self_collide	<input type="checkbox"/> False
enable_wind	<input type="checkbox"/> False
▶ pose	
▶ link	panda::panda_li...
▶ link	panda::panda_li...
▶ link	panda::panda_li...
▶ link	panda::panda_li...
▶ link	panda::panda_li...
▶ link	panda::panda_li...
▶ link	panda::panda_li...
▶ link	panda::panda_li...

The main 3D view shows the Panda robot arm in a white bounding box on a grid floor. A blue line indicates the current pose, and a green line indicates a target pose. The robot is positioned at the origin of the coordinate system.

3. [0, -1, 1, -2, 4, 8, 5]



4. [0, -6, 1, -2, 4, 8, 5]



5. [0, -1, 1, -4, 4, 8, 3]

