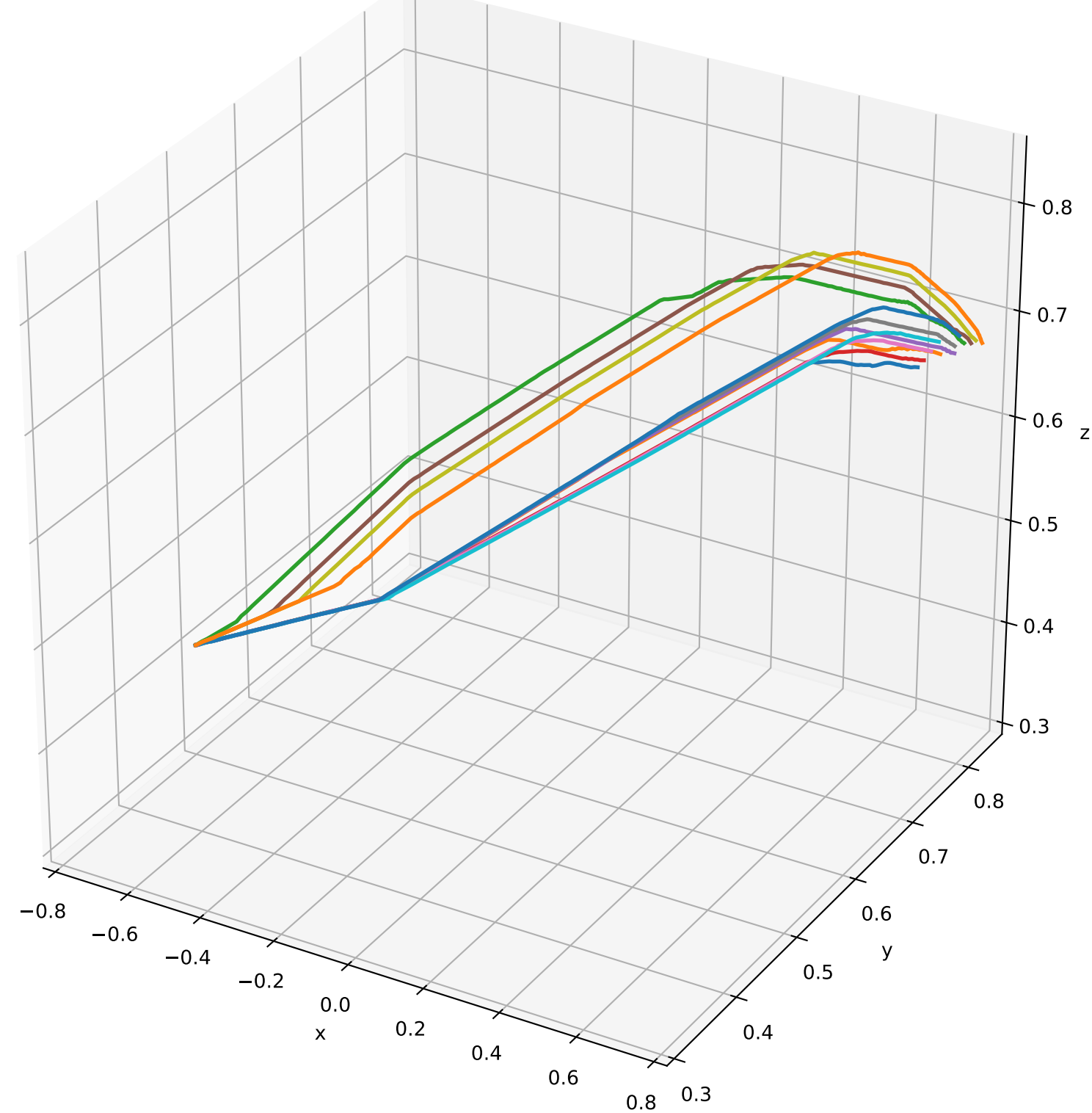
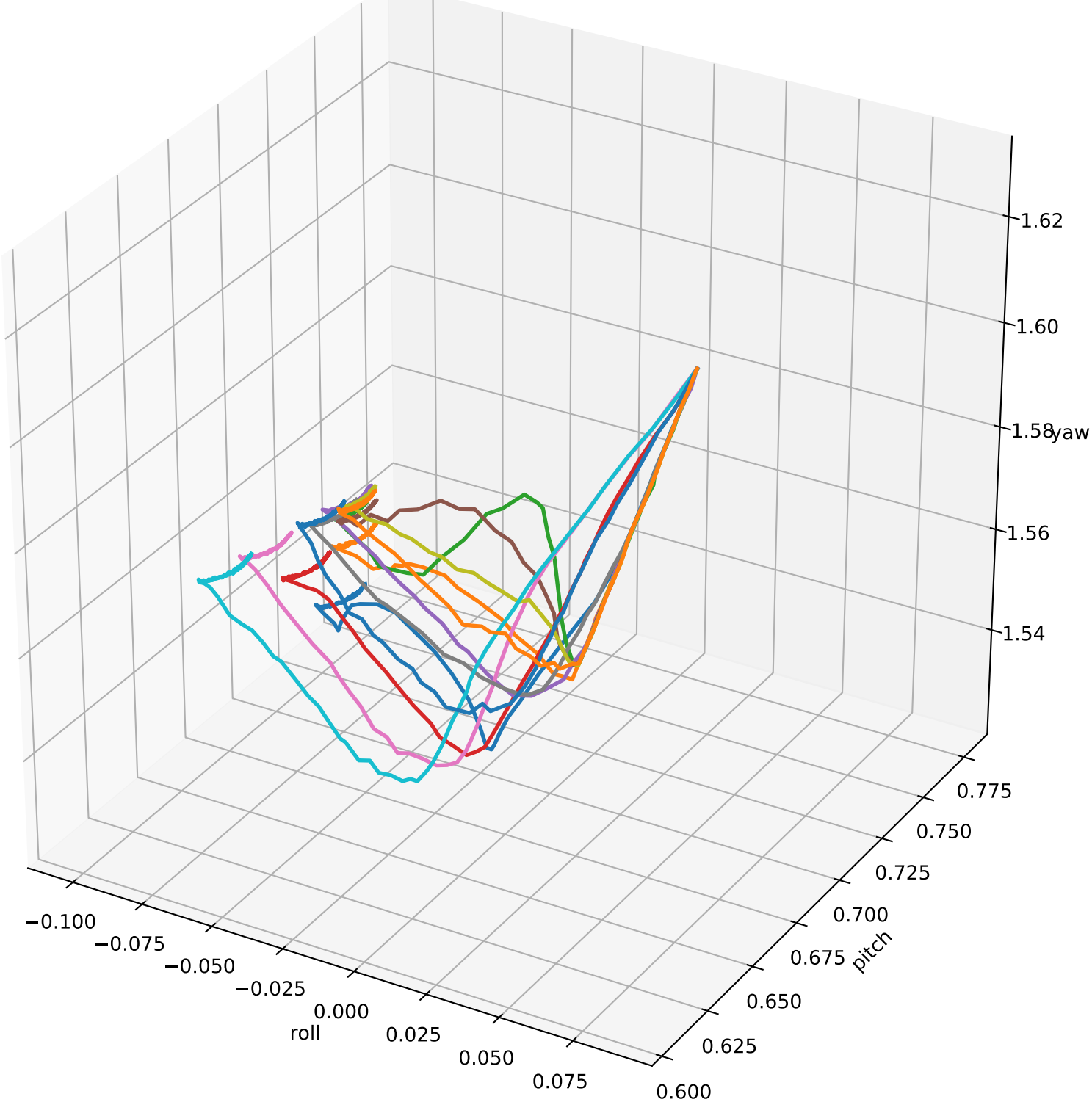


Derivative learning method, experiment 3
init_pose = [-0.659, 0.429, 0.448, 0.087, 0.636, 1.632]
goal_pose = [0.783, 0.792, 0.669, -0.180, 0.693, 1.547]

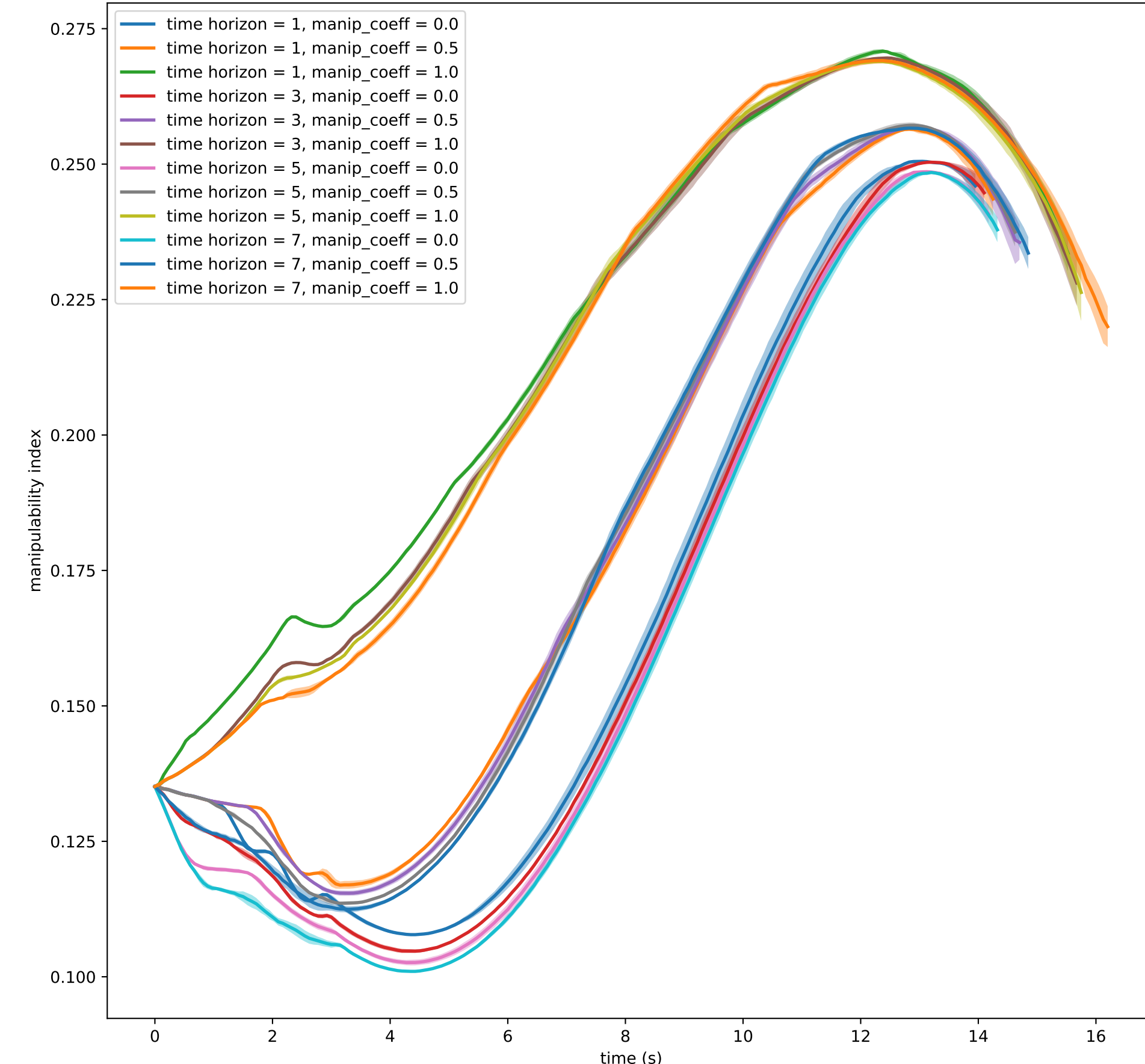
trajectory (translation)



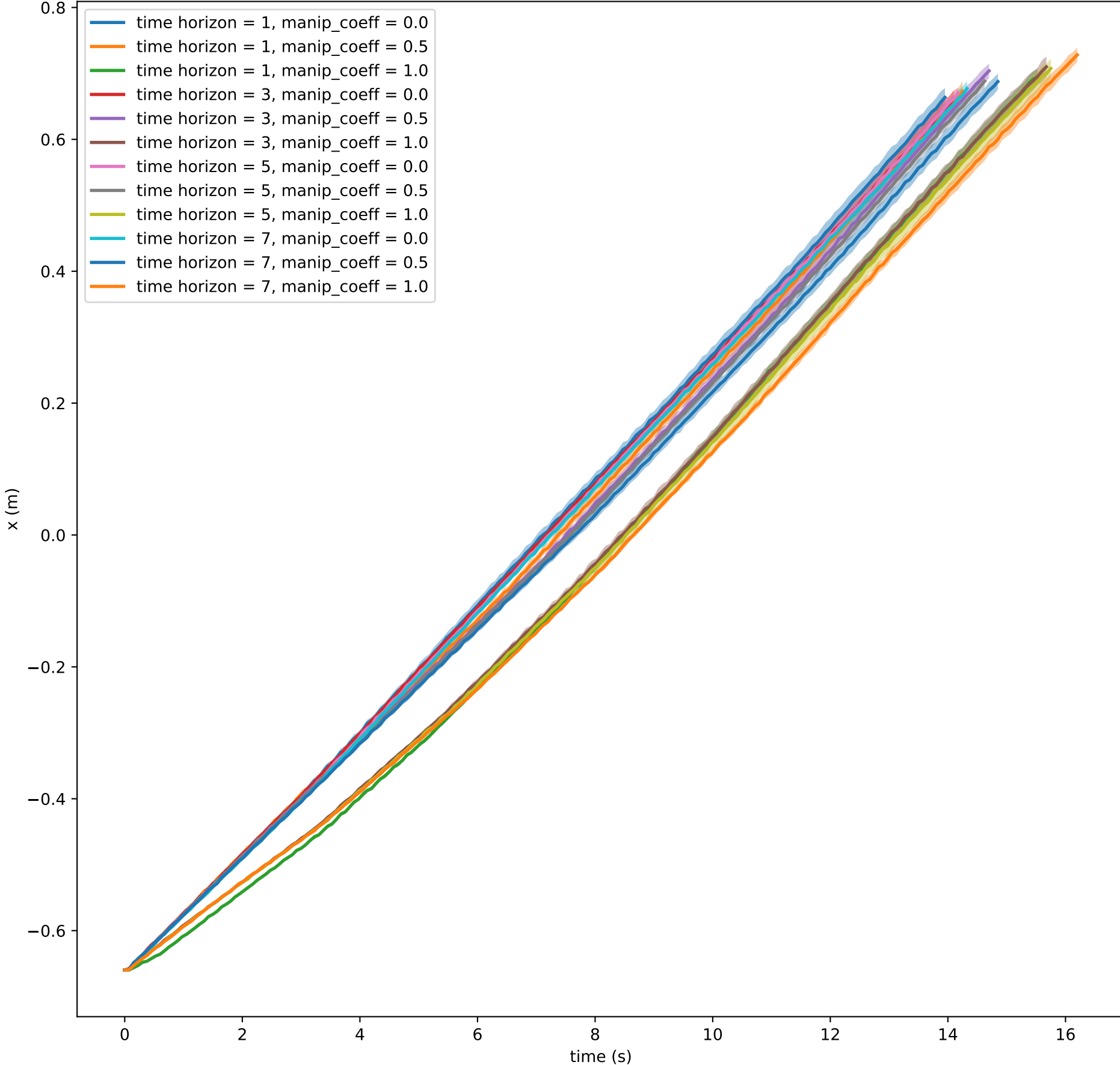
trajectory (orientation)



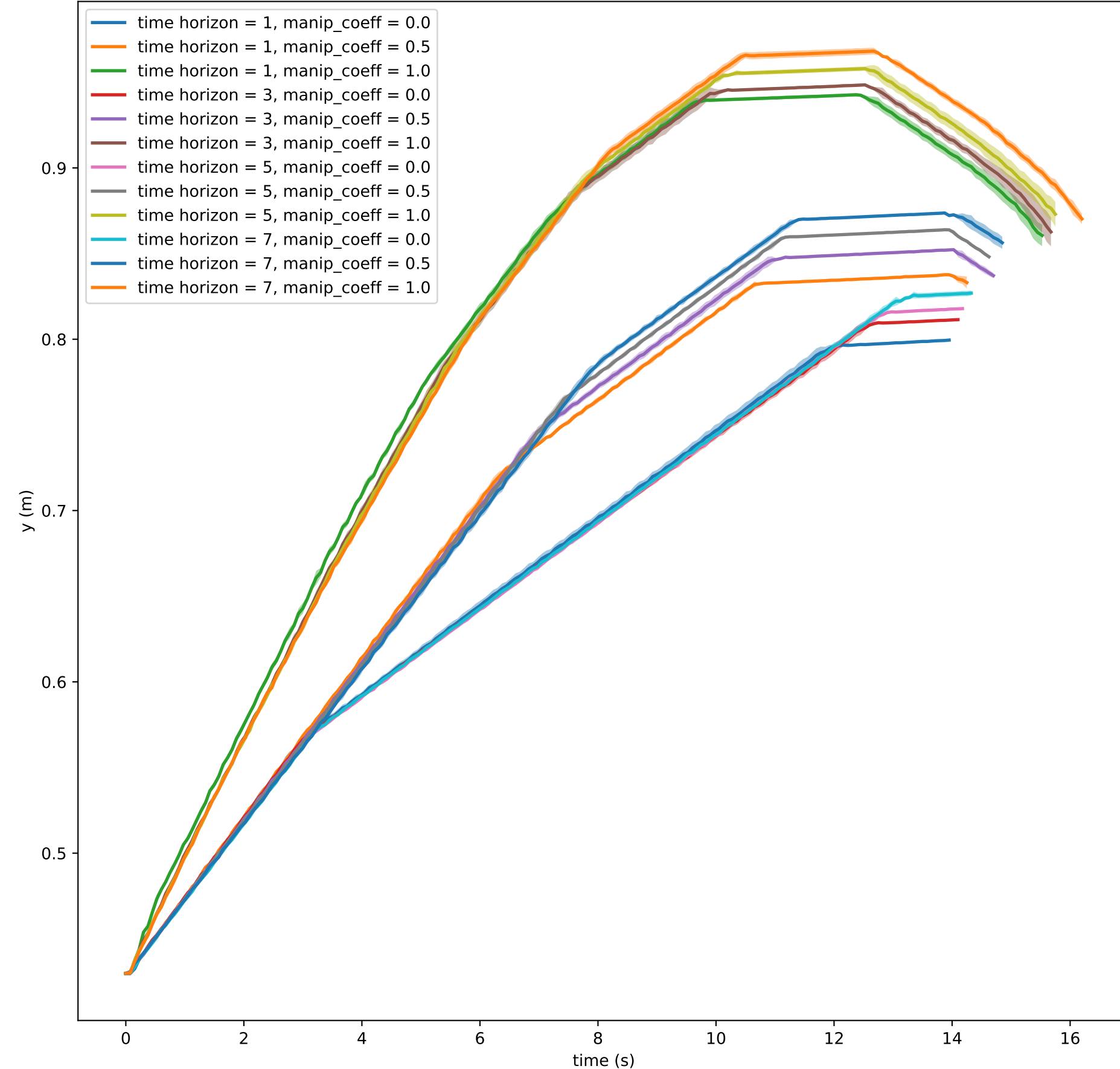
manipulability index



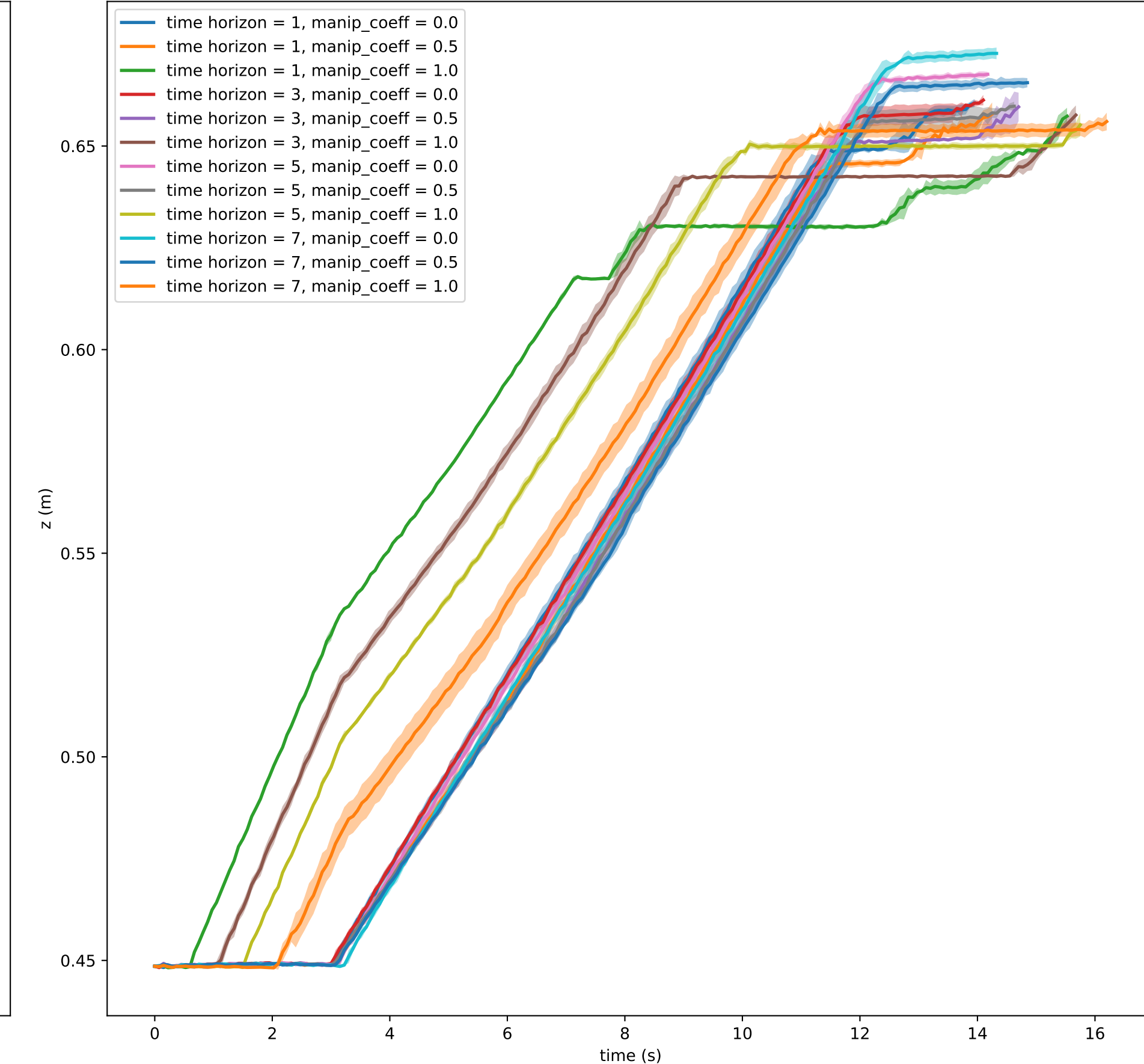
trajectory (x)



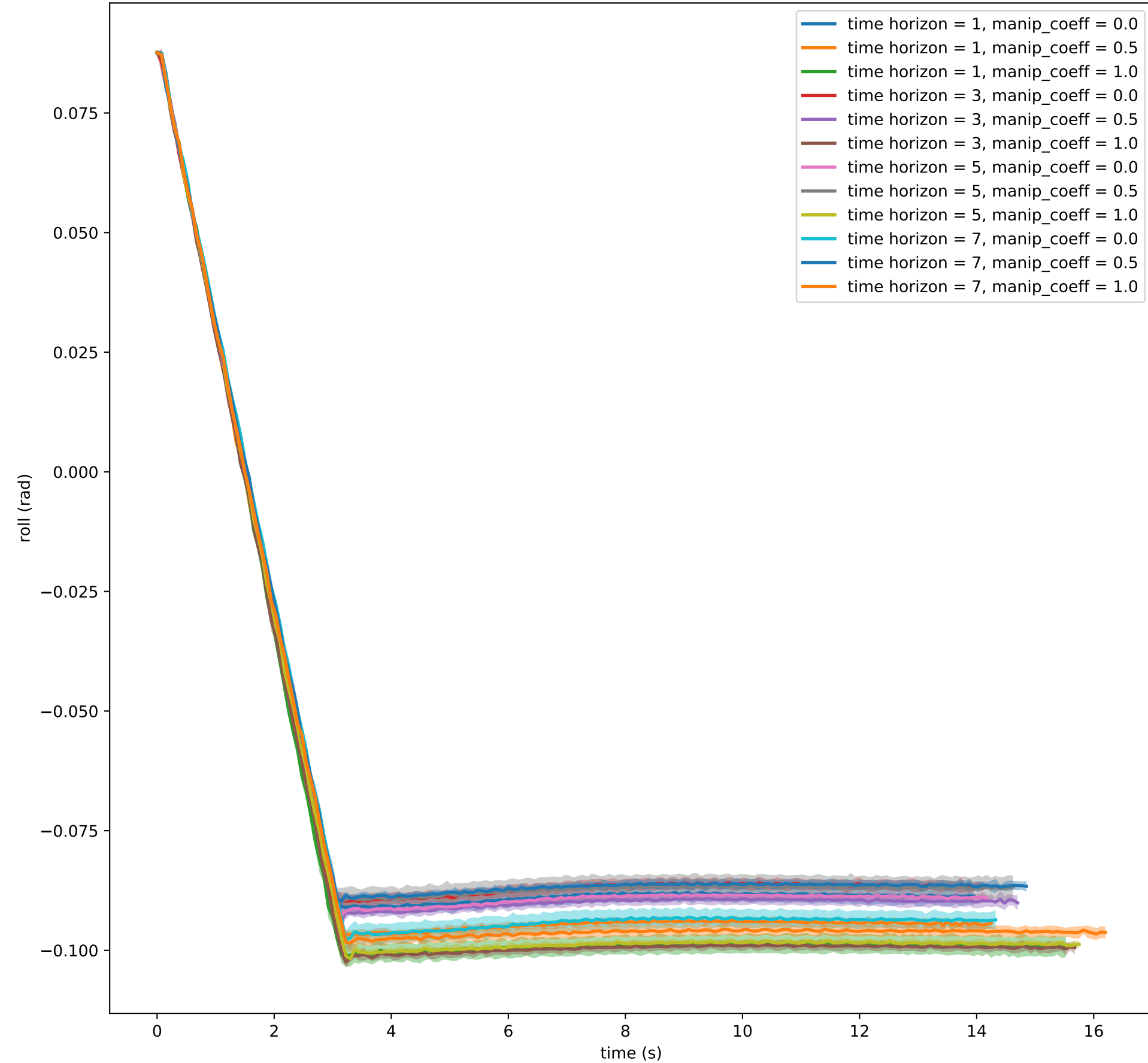
trajectory (y)



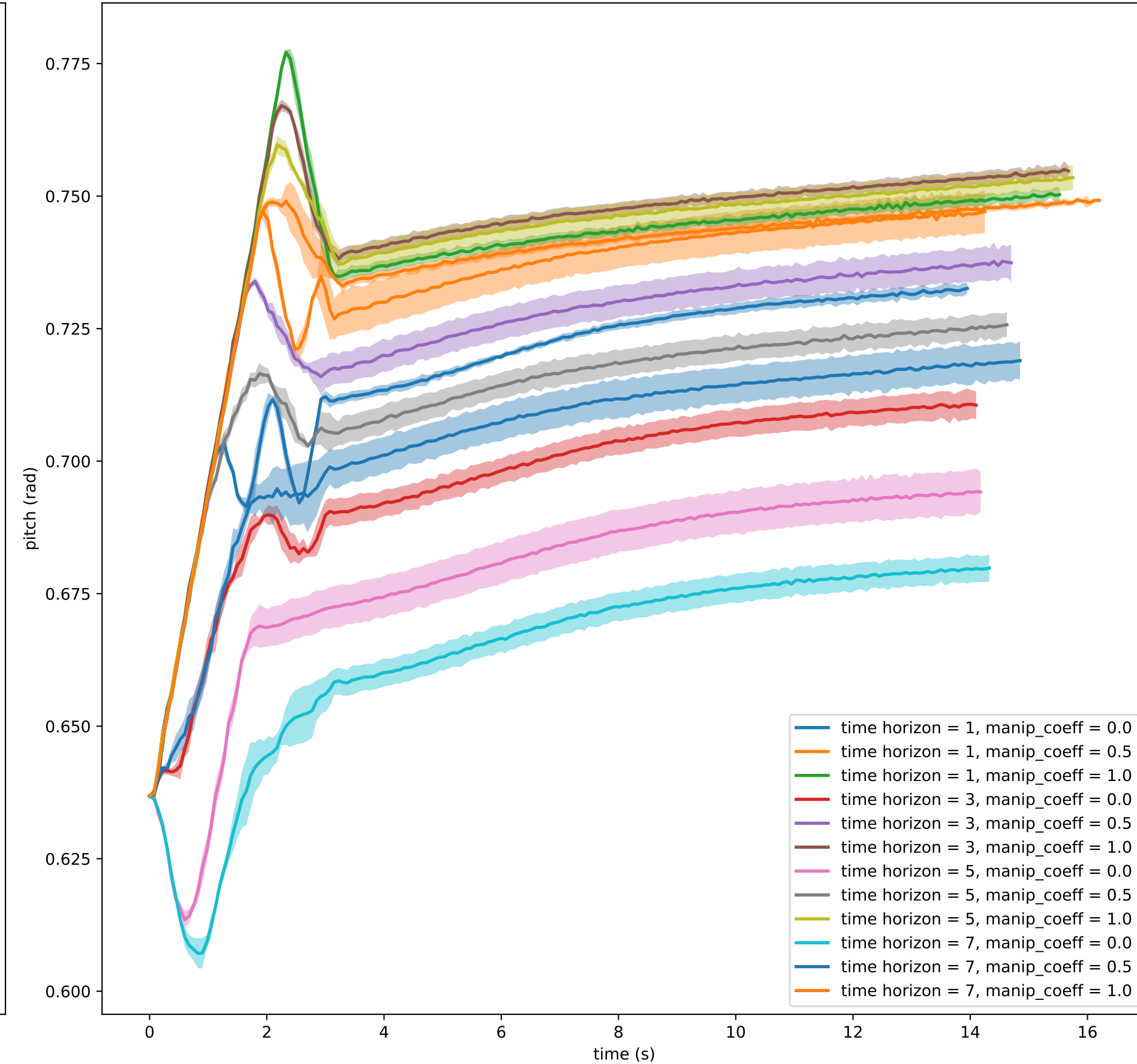
trajectory (z)



trajectory (roll)



trajectory (pitch)



trajectory (yaw)

