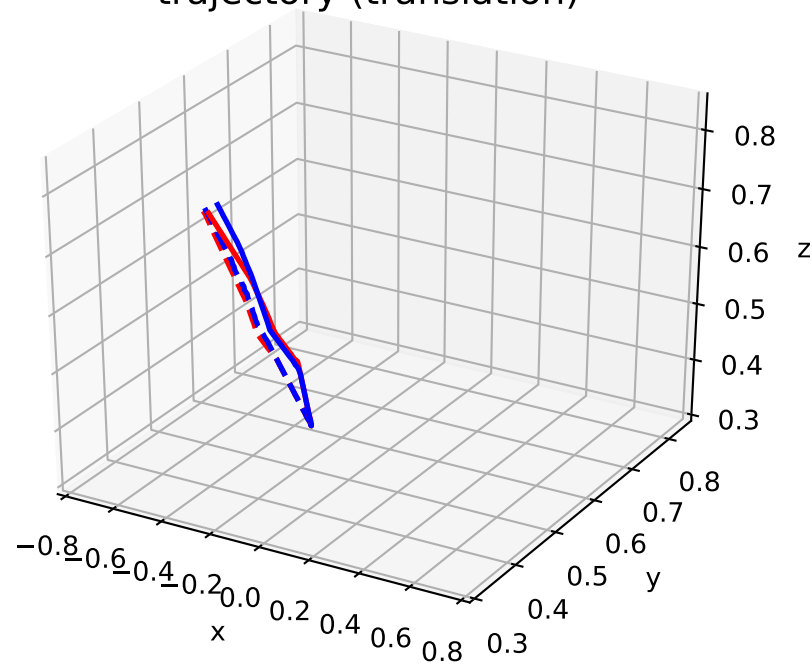
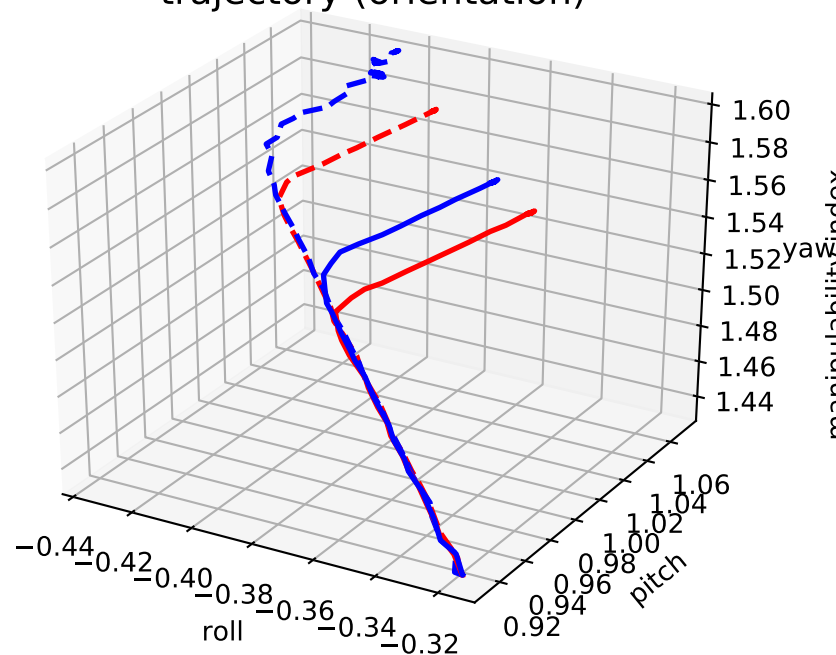


Manipulability Maximization $\alpha = 1.0$
init_pose = [-0.317, 0.593, 0.300, -0.316, 0.912, 1.430]
goal_pose = [-0.510, 0.419, 0.818, -0.317, 1.088, 1.613]

trajectory (translation)



trajectory (orientation)



manipulability index

