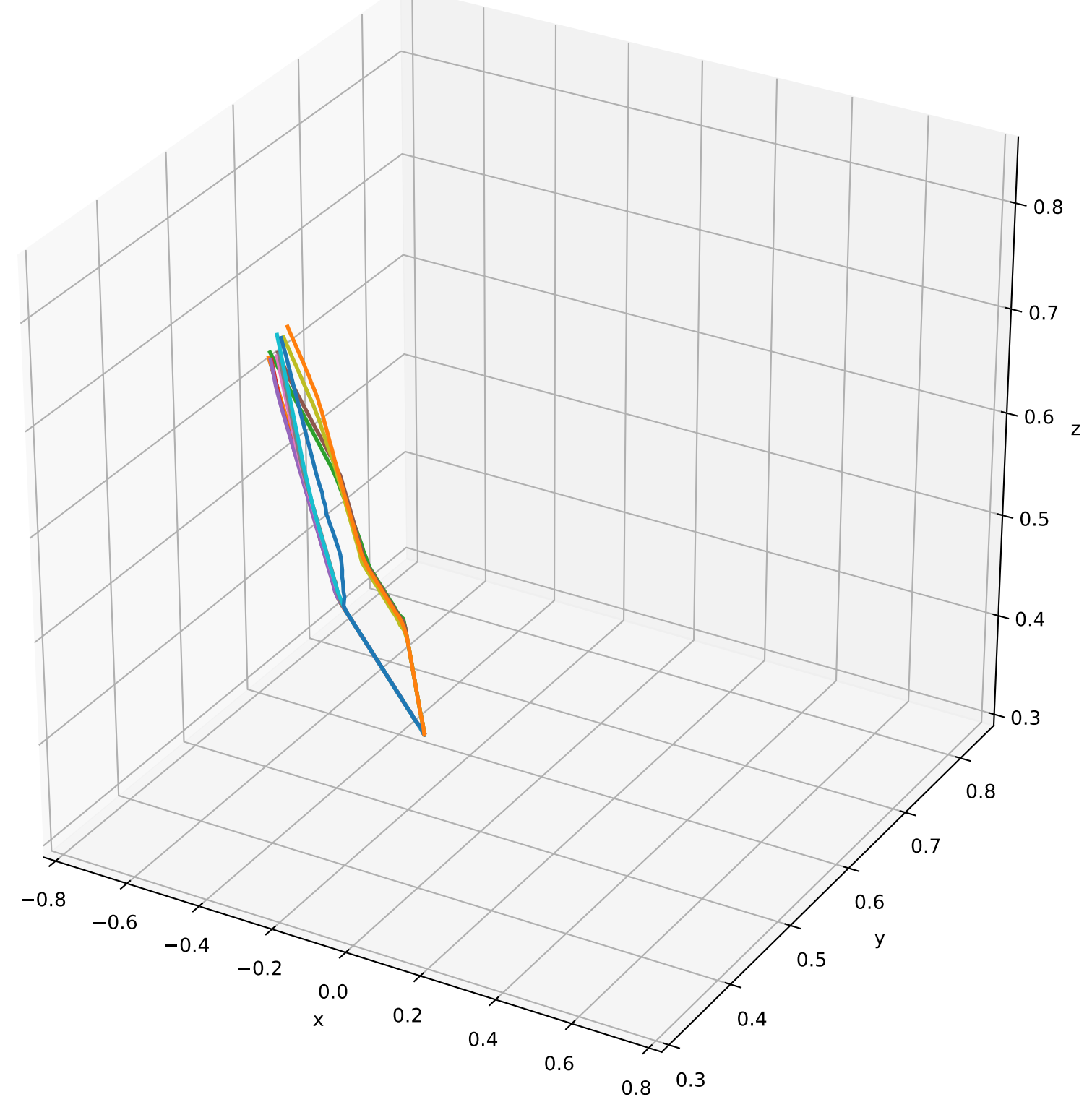
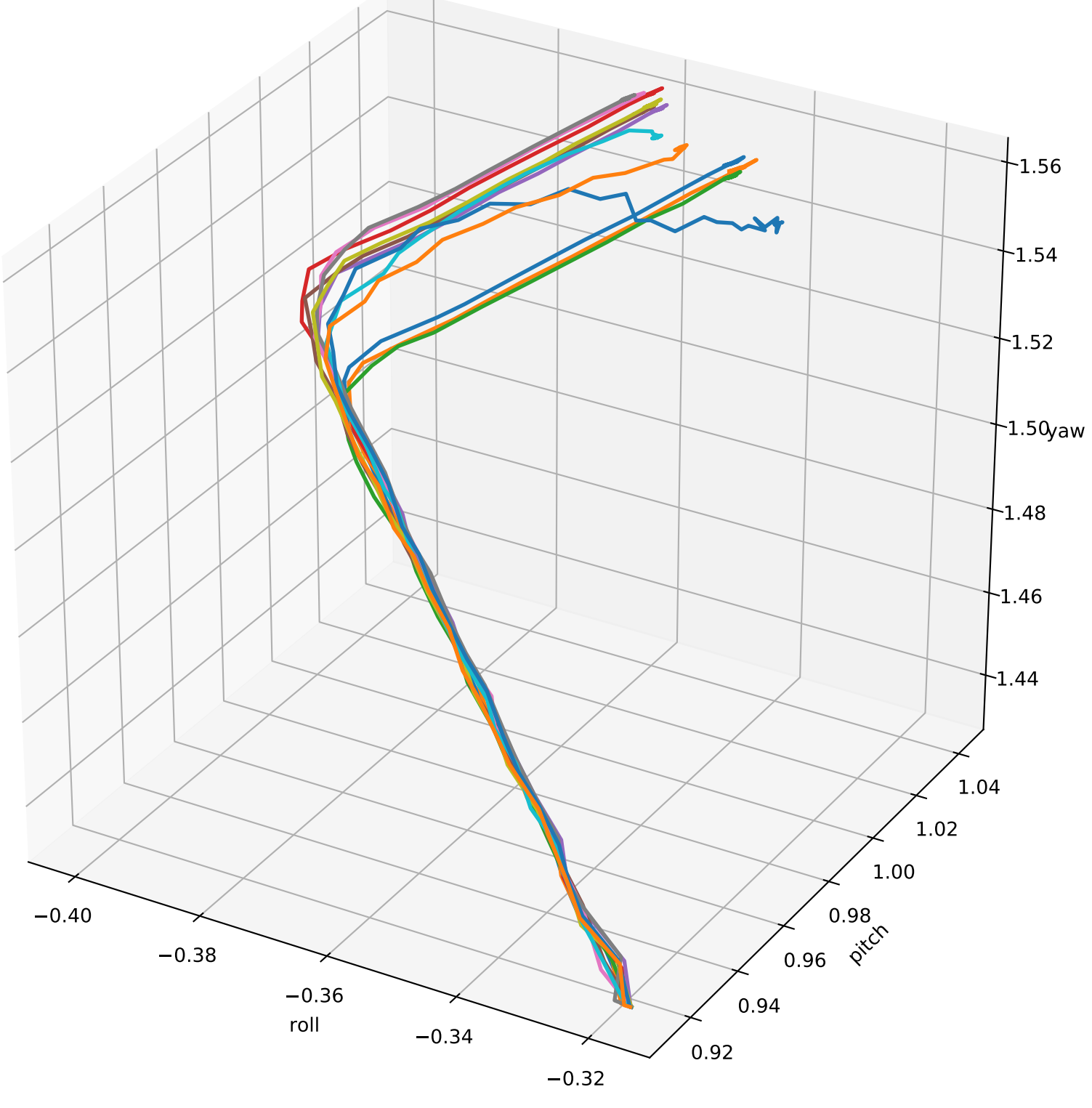


Derivative learning method, experiment 5
init_pose = [-0.317, 0.593, 0.300, -0.316, 0.912, 1.430]
goal_pose = [-0.510, 0.419, 0.818, -0.317, 1.088, 1.613]

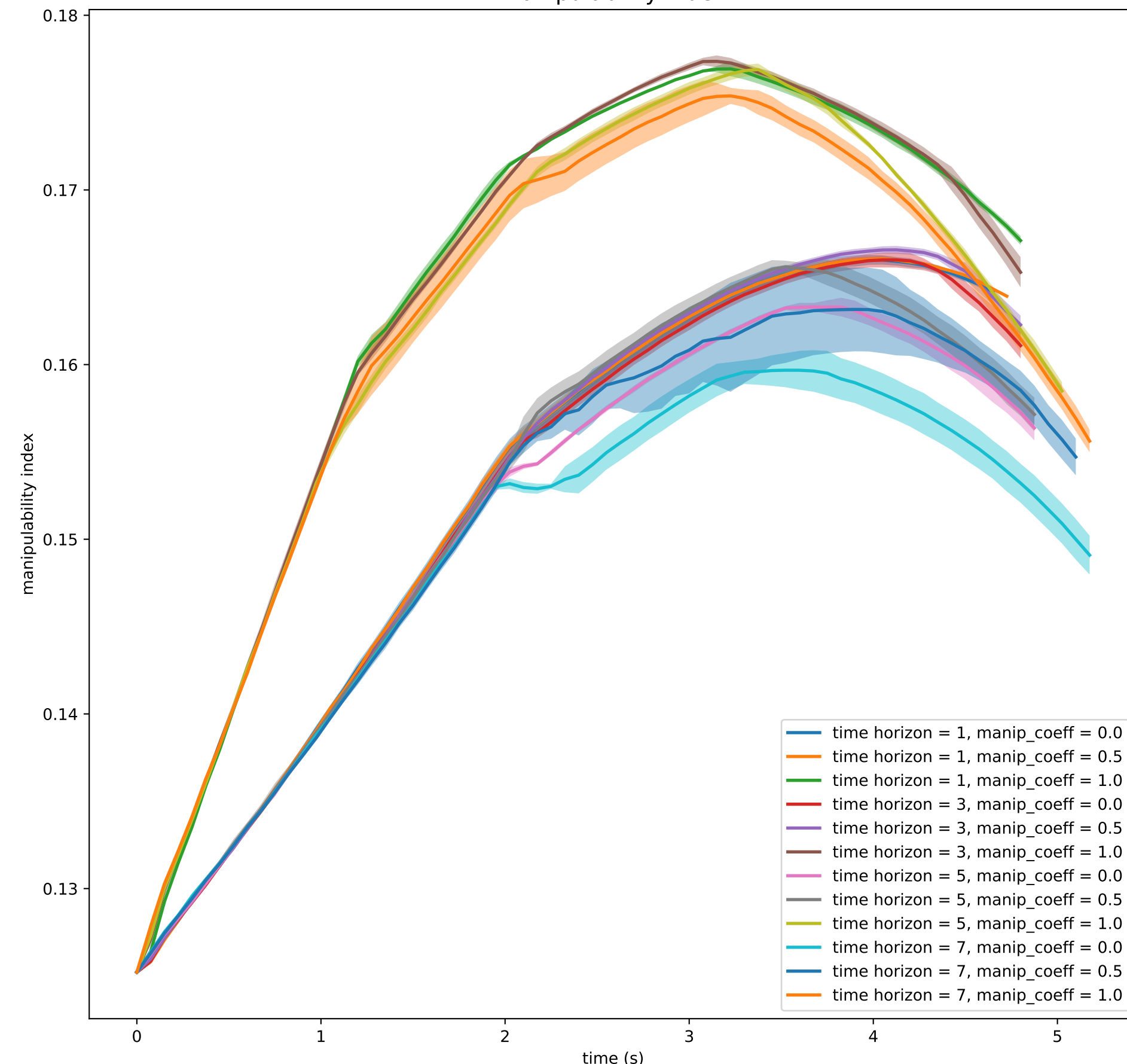
trajectory (translation)



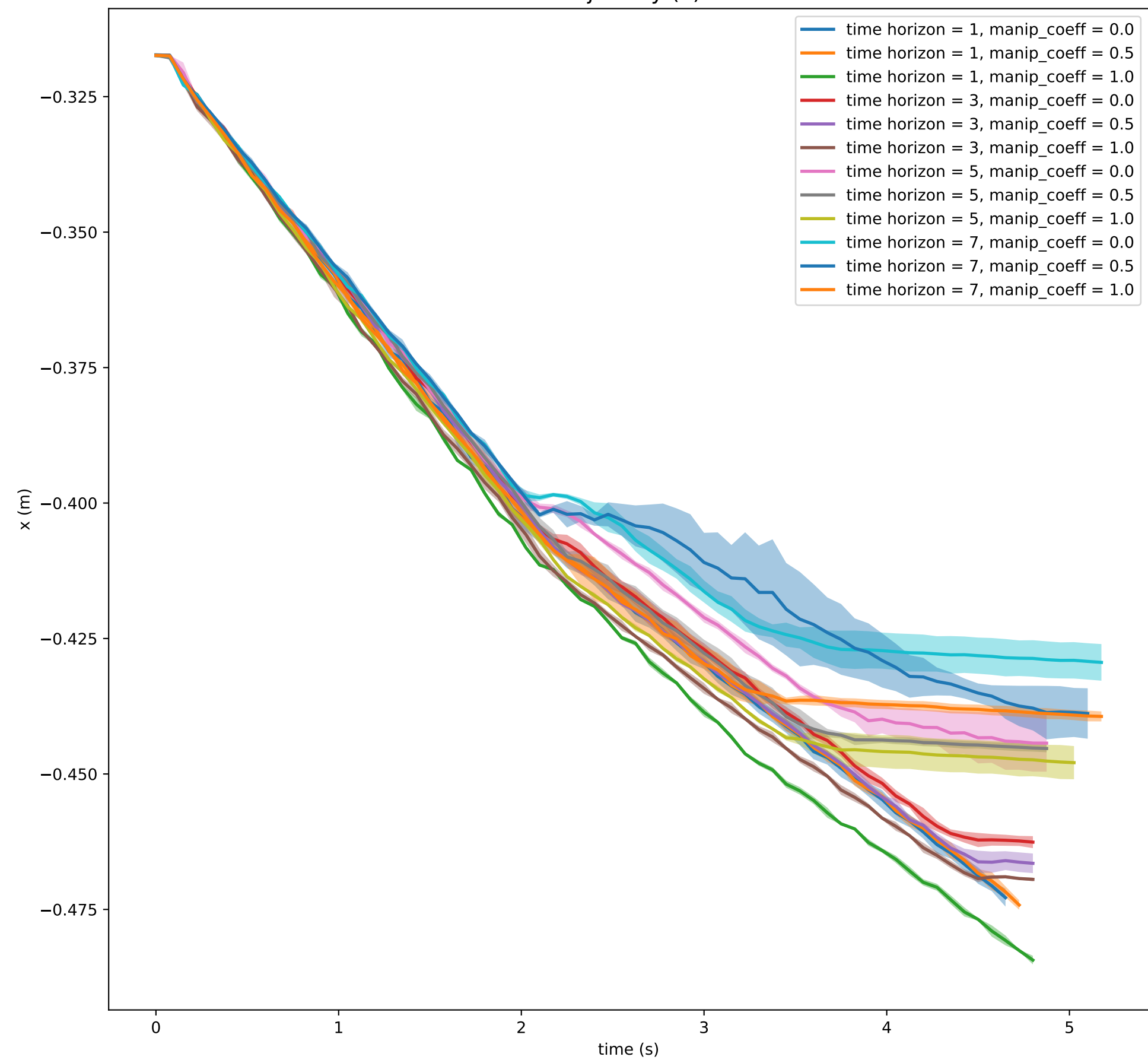
trajectory (orientation)



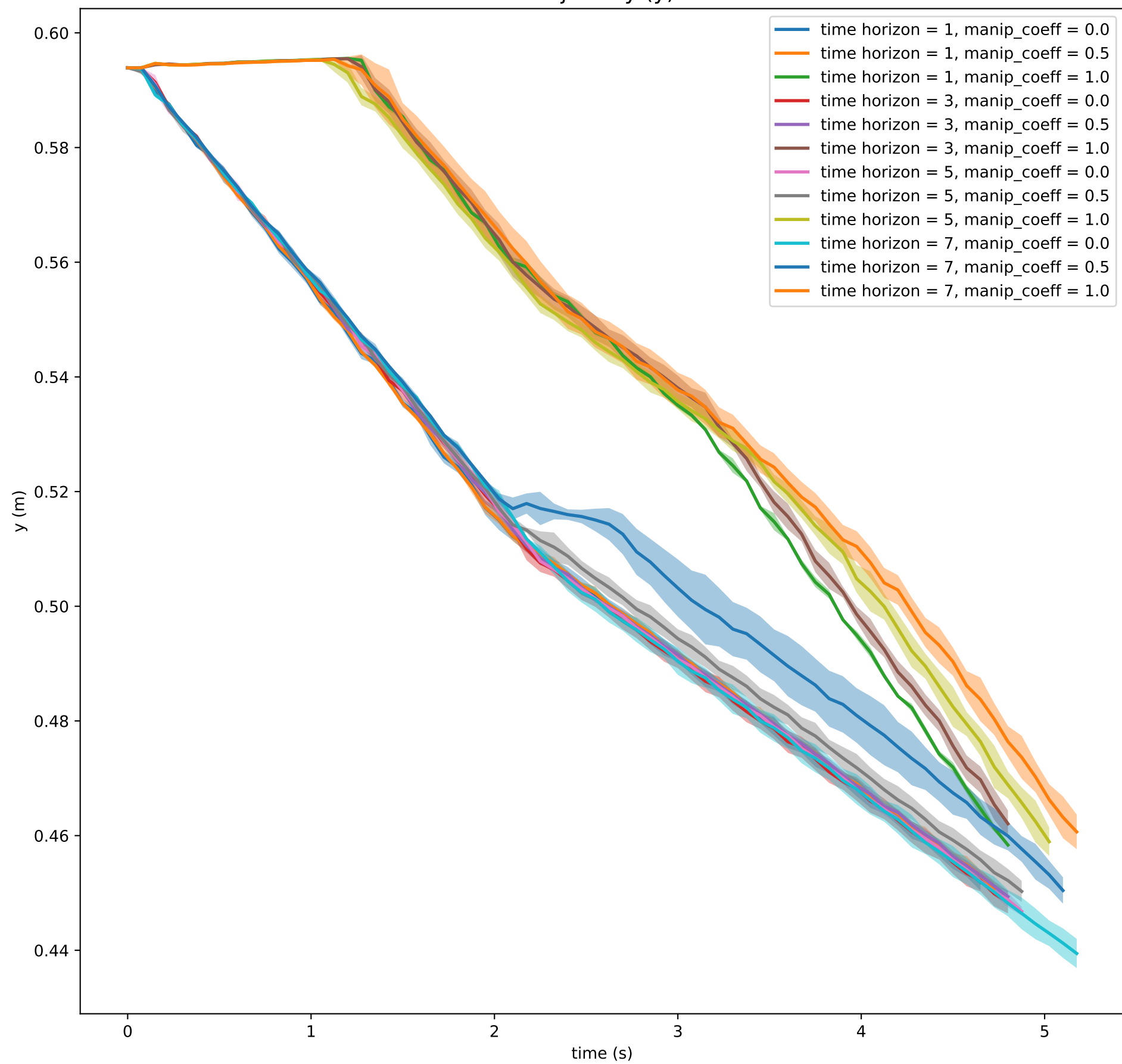
manipulability index



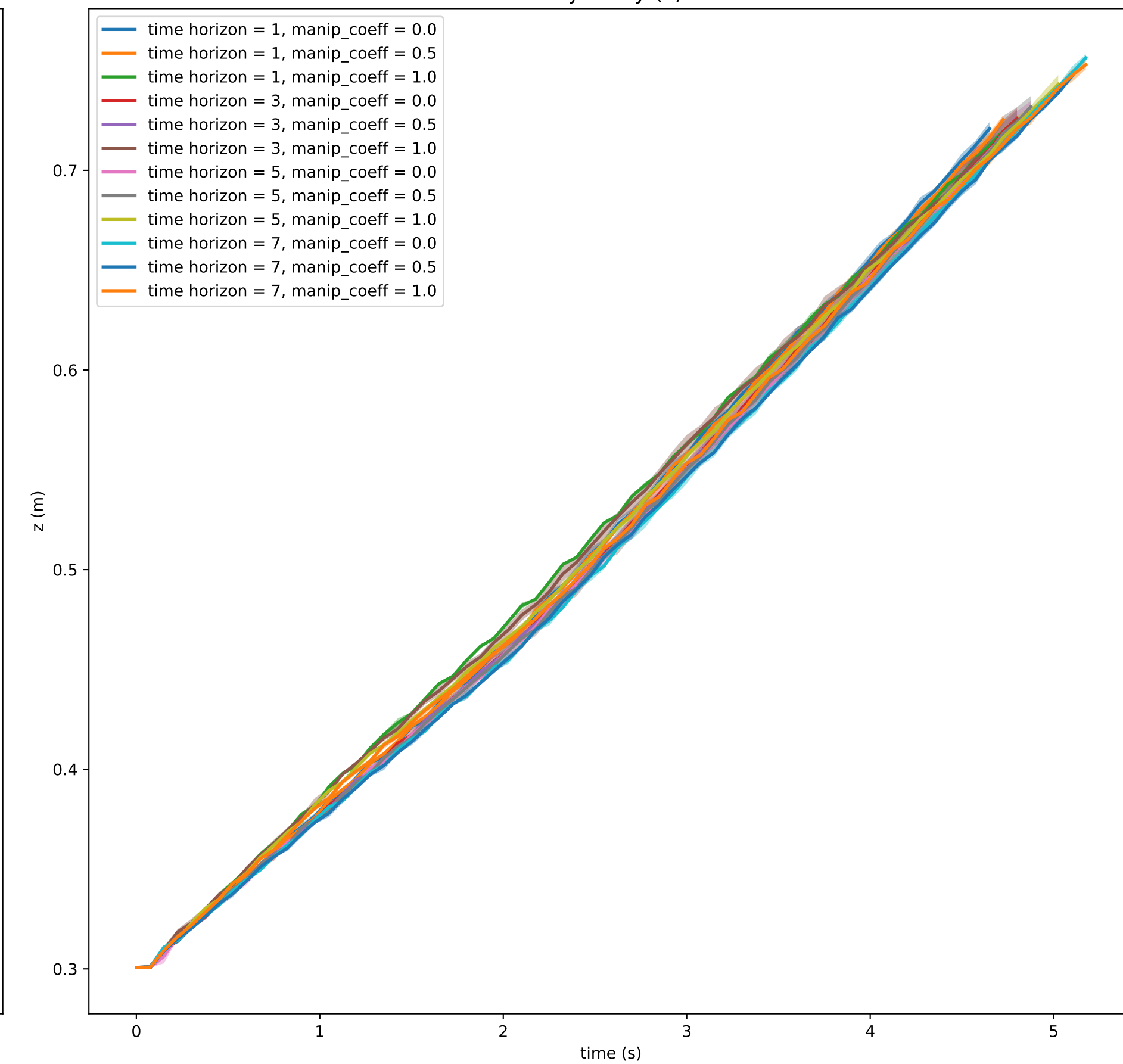
trajectory (x)



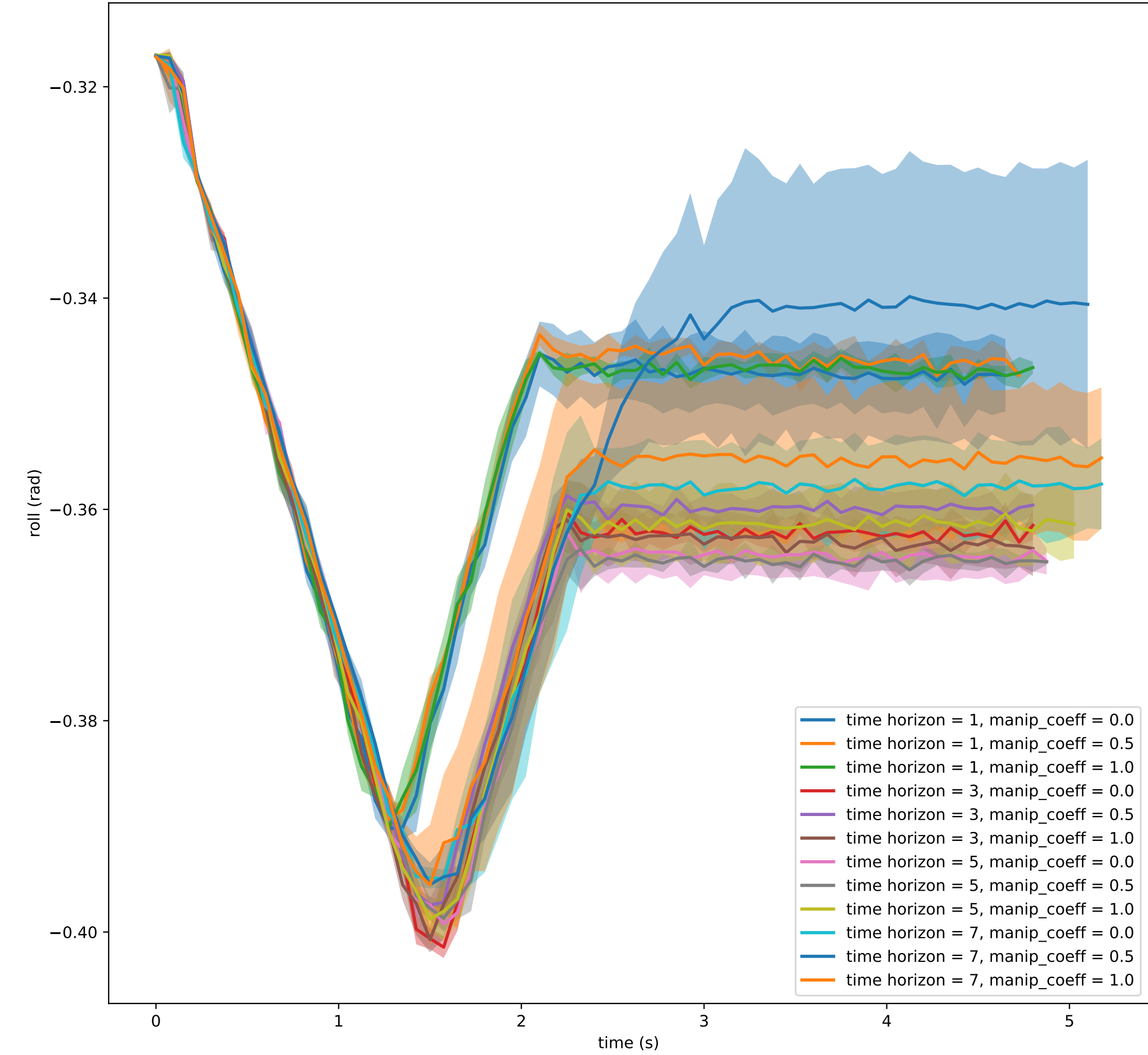
trajectory (y)



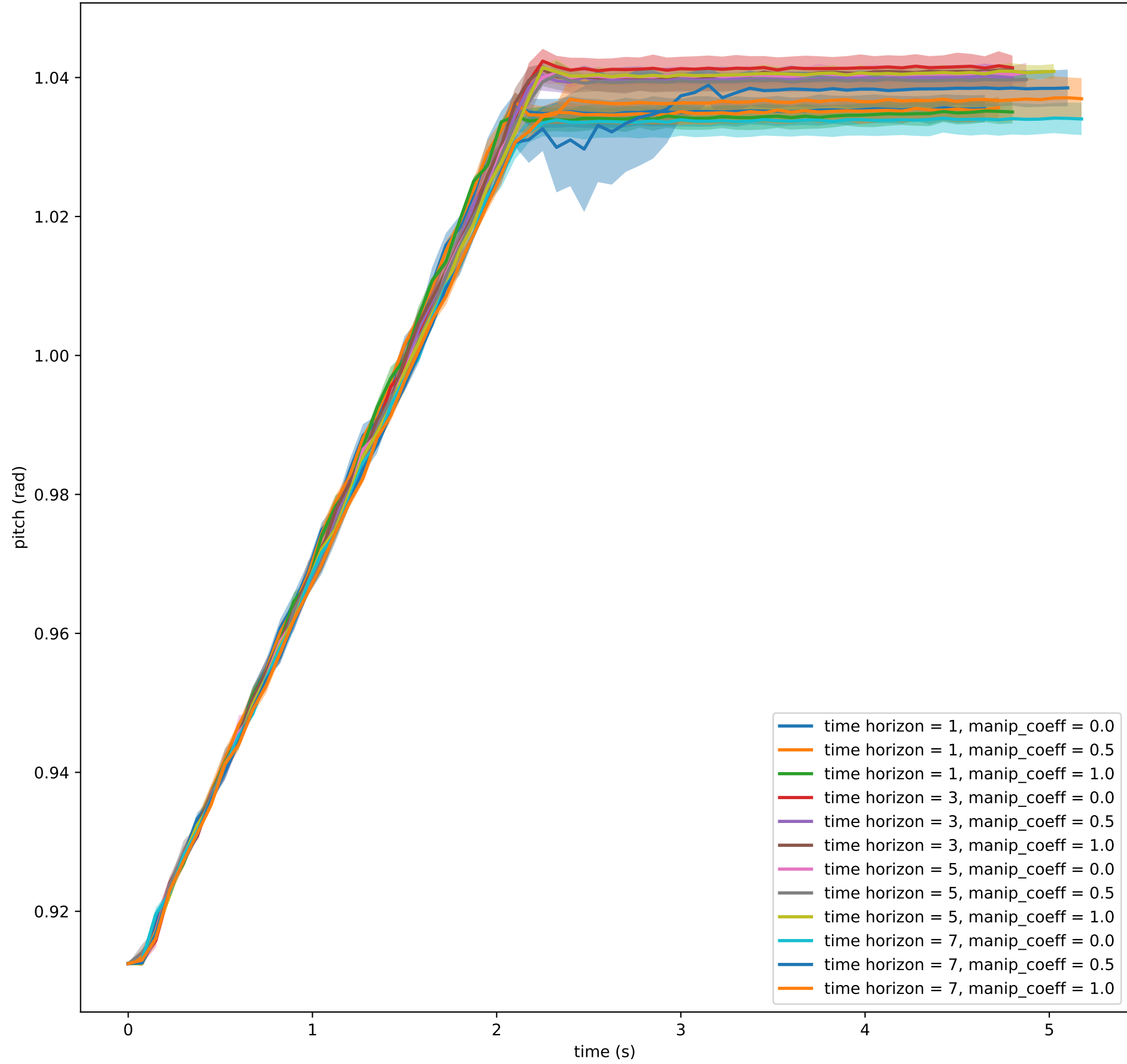
trajectory (z)



trajectory (roll)



trajectory (pitch)



trajectory (yaw)

