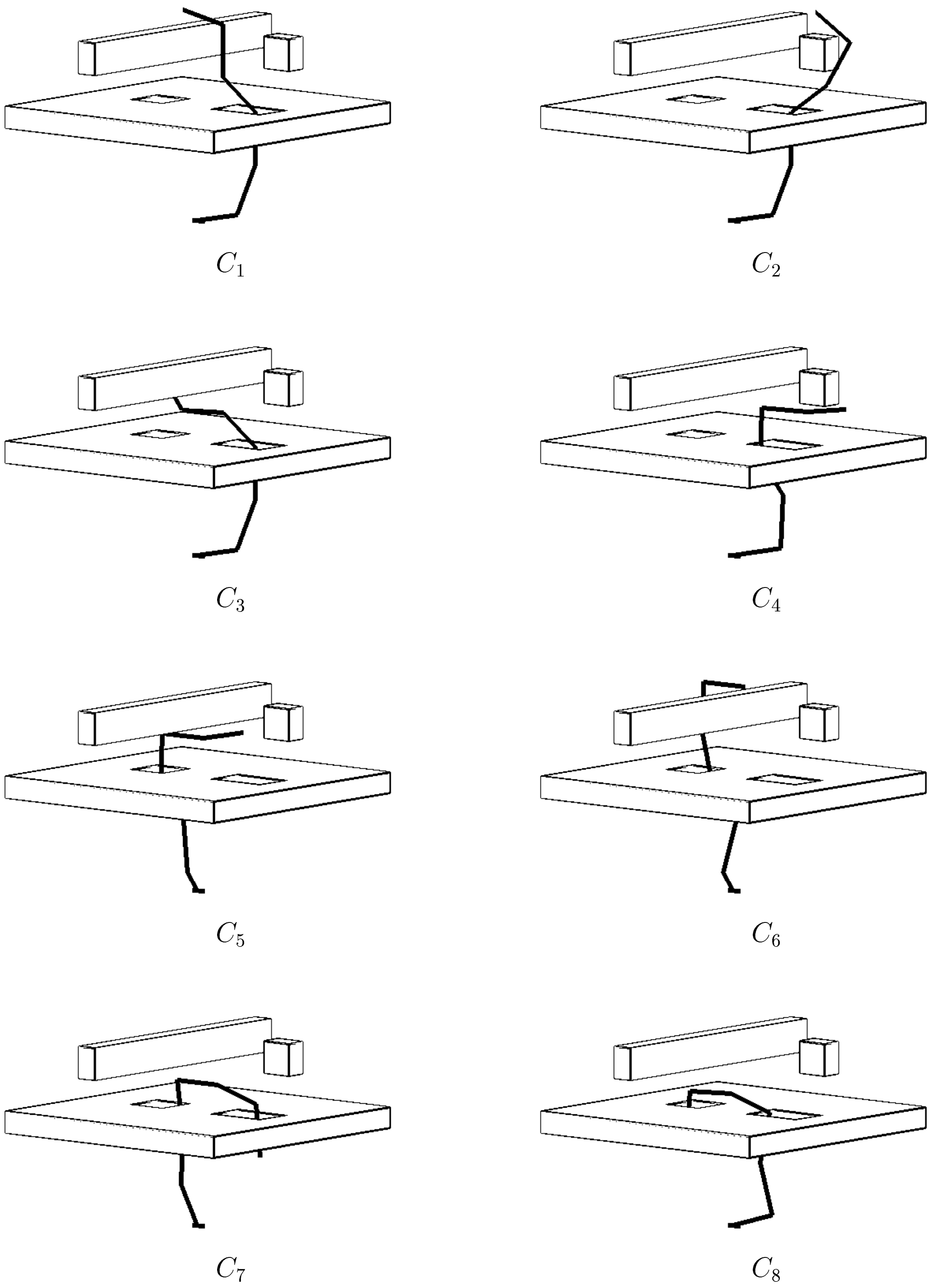

Figure 3.11: Scene 4, with a fixed-base robot which has 6 spherical joints (12 dof)

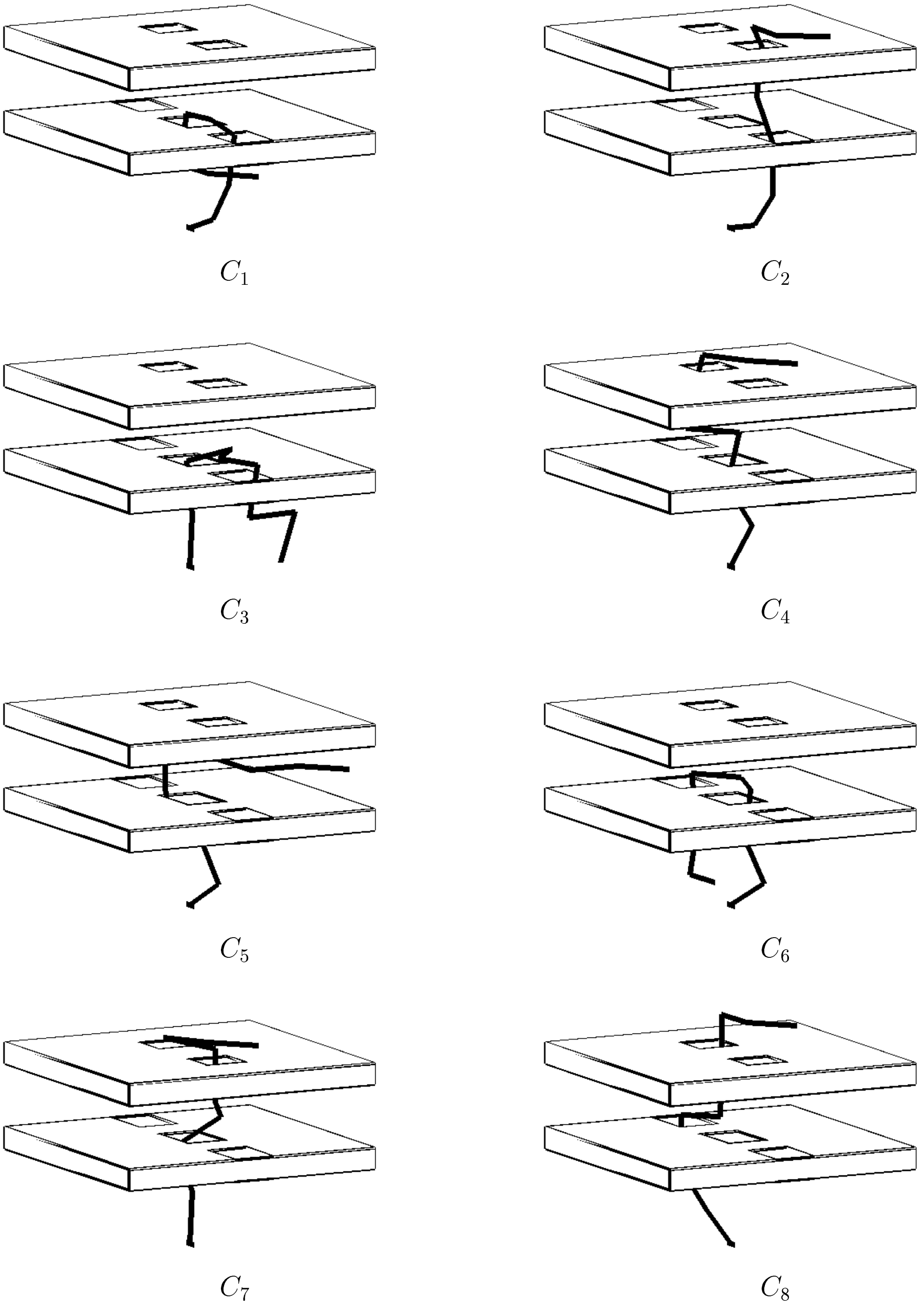

Figure 3.12: Scene 5, with a fixed-base robot which has 8 spherical joints (16 dof)