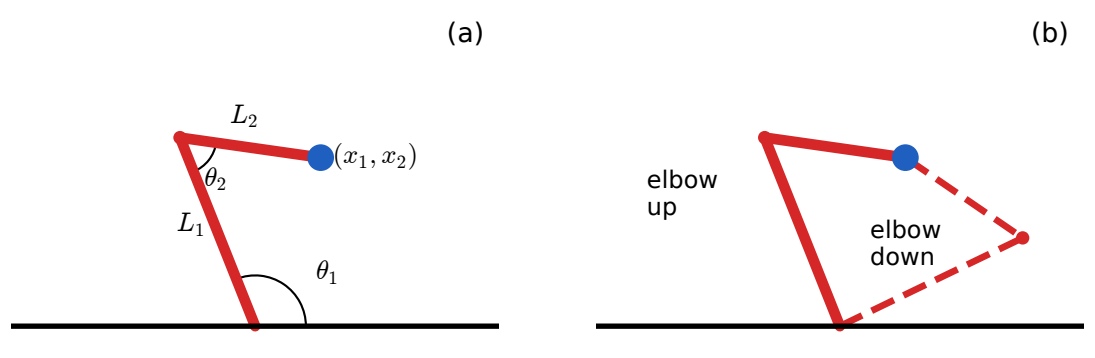

(a)
L_2
(x_1, x_2)
θ_2
L_1
θ_1
(b)
elbow
up
elbow
down