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| Task. No.: | 1 | Points: | 5 | Pick and place application |

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| Objectives:  1. Use the real robot. 2. Jog the robot using the move tab. 3. Operate gripper. |

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| Description: The aim of this exercise is to pick and object from one location and place it on another location. |

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| Step | Action |
| 1 | Power up and initialize robot arm. |
| 2 | Teach waypoints using freedrive or jog function in the move tab. |
| 3 | Define motions needed for the application. |
| 4 | Add *set* command to open and close the gripper. |

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