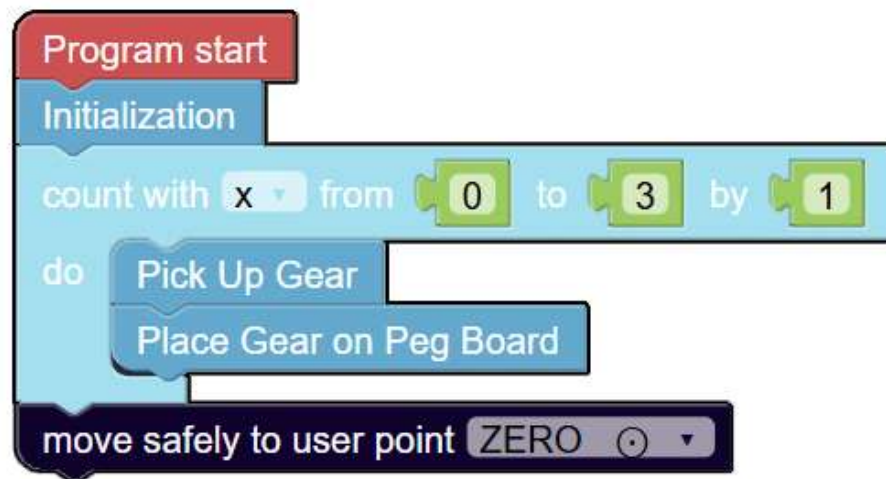


# ORA Expansion Gripping: Getting a Grip from Within

Ozobot Editor Blocks



to Pick Up Gear

move to coordinate (x = 241 , y = -243 , z = 60 ) [mm]

with tool angle (roll = -180 , pitch = 0 , yaw = ) [°]

movement type: linear

set finger gripper CLOSED

move to coordinate (x = 241 , y = -243 , z = pickUpZvalue ) [mm]

with tool angle (roll = -180 , pitch = 0 , yaw = ) [°]

movement type: linear

set finger gripper OPEN

move to coordinate (x = 241 , y = -243 , z = 60 ) [mm]

with tool angle (roll = -180 , pitch = 0 , yaw = ) [°]

movement type: linear

change pickUpZvalue by -1 × gearThickness

move safely to user point HOME

set finger gripper OFF

to Place Gear on Peg Board

move to coordinate (x = 230 , y = 0 , z = 85 ) [mm]

with tool angle (roll = -180 , pitch = -90 , yaw = 90 ) [°]

movement type: linear ▾

move to coordinate (x = 230 , y = 143 , z = 85 ) [mm]

with tool angle (roll = -180 , pitch = -90 , yaw = 90 ) [°]

movement type: linear ▾

set finger ▾ gripper CLOSED ▾

set finger ▾ gripper OFF ▾

move to coordinate (x = 230 , y = 115 , z = 85 ) [mm]

with tool angle (roll = -180 , pitch = -90 , yaw = 90 ) [°]

movement type: linear ▾

move safely to user point HOME ⦿ ▾