

# Fetch Sensors

## Cheat Sheet

### Goal

Utilize the robot's sensors to guide the gripper in transporting all objects to the container.



### Word Bank

Environment (env)

FetchOrganizeSensorsEnv

Distance Threshold

Sensor Threshold

Open Grip Action

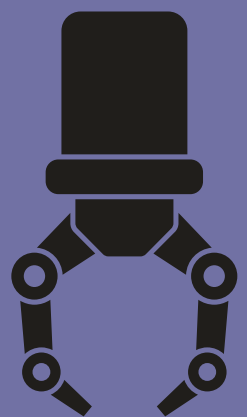
Close Grip Action

Ascend Action

Descend Action

### Steps

- 1) Lower the gripper to scanning height
- 2) Sweep left across the environment
- 3) Continuously read the forward facing sensor
- 4) If an object is detected, approach it



- 5) Open the gripper and grasp the object
- 6) Lift and navigate to the container
- 7) If close enough to the container, release the object
- 8) Repeat the process