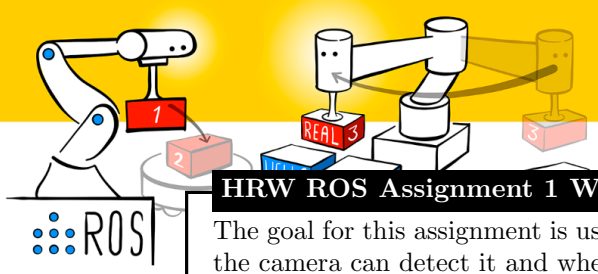

HRW ROS Assignment 1 Week 6 Part 1

The goal for this assignment is use the conveyor belt to bring a part (the white box) to the area where the camera can detect it and where `robot1` can pick it up.
You can reach this goal by following the steps below:

- Open the FlexBE App, by executing:

  ```
  $ rosrun flexbe_app run_app --offline
  ```

  And load the behavior "Final Project".

- Edit the state machine so that:
  - After "Move R1 Home", a new state starts the conveyor belt.
  - After "Stop feeder" another new state stops the conveyor belt.

  You may revisit videos 6.4.2 and 6.4.3 to see what state type to use and how to configure it.

- Now reconnect the states in the state machine so that if everything goes ok (so no state results in the "failed" outcome), the last active state is "Move R1 back Home" and, as a result of executing the behavior, `robot1` holds the part.

- Save your changes in the behavior and close the FlexBE App.

- Start the final project environment simulation environment using:

  ```
  $ roslaunch hrwros_week6 hrwros_final_project.launch
  ```

- On another CCS terminal, open the flexbe App for behavior execution using:

  ```
  $ roslaunch flexbe_app flexbe_full.launch
  ```

This completes HRW ROS Assignment 1 Week 6