def gripper\_motion():

import RPi.GPIO as GPIO

from time import sleep

Dir= #GPIO PIN

Step= #GPIO PIN

CW=1

CCW=0

Spr= #number of steps taken by motor to make one complete revolution

GPIO.setmode(GPIO.BCM)

GPIO.setup(Dir,GPIO.OUT)

GPIO.setup(Step,GPIO.OUT)

step\_count=Spr/"Factor"

delay= #Time elapse

GPIO.output(Dir,CW)

for x in range(step\_count):

GPIO.output(step\_count,GPIO.HIGH)

sleep(delay)

GPIO.output(step\_count,GPIO.LOW)

sleep(delay)

sleep("TIME")

GPIO.output(Dir,CCW)

for x in range(step\_count):

GPIO.output(step\_count,GPIO.HIGH)

sleep(delay)

GPIO.output(step\_count,GPIO.LOW)

sleep(delay)

GPIO.cleanup()