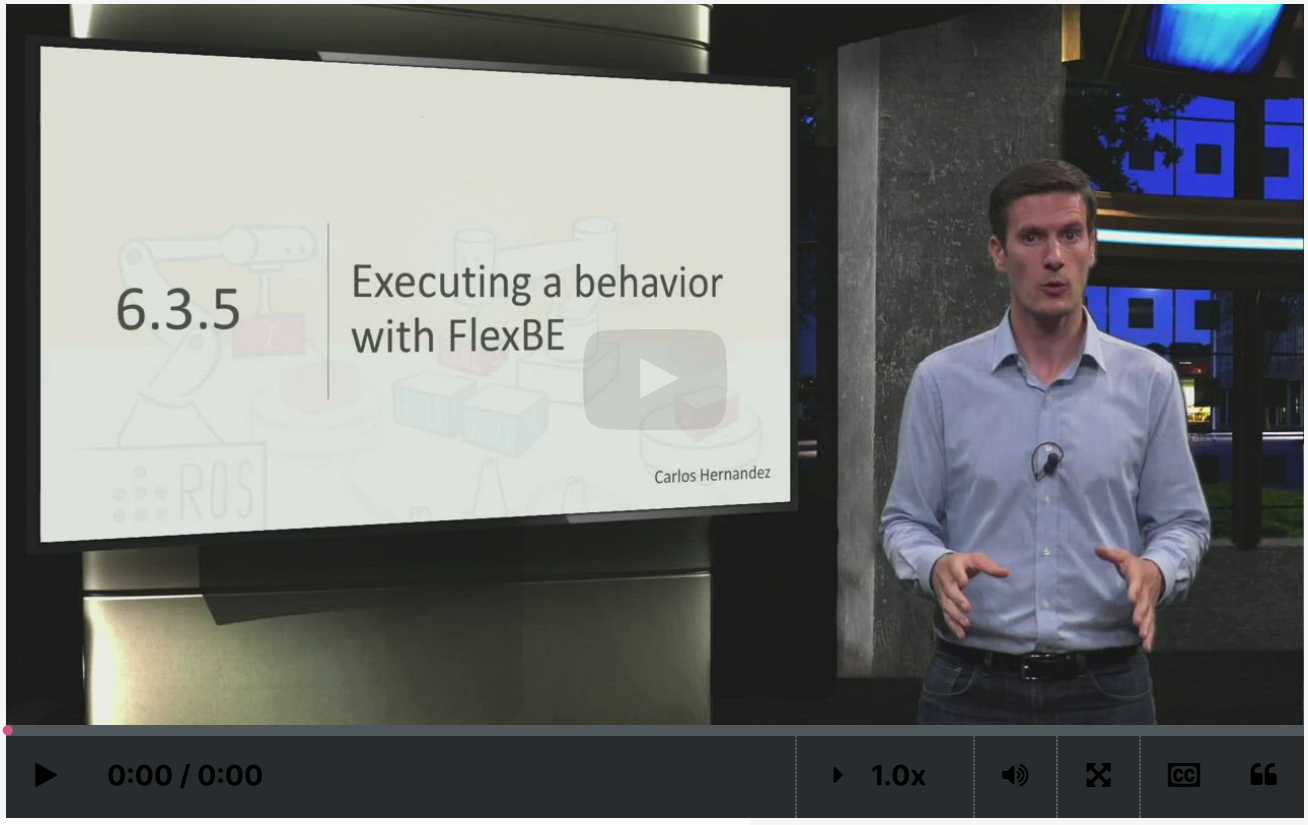
In the previous video you designed a FlexBE behavior. In this video we will show you how to execute it.

Important Note:
In the FlexBE version we are using in this edition (different from the one in the video) to start Flexbe App for behavior execution you need to execute:

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

Executing a behavior with FlexBE



Video ▼ Subtitles ▼

Other ▼

From the previous video's you already know:

- How to define user data and behavior variables in a FlexBE behavior.
- How to configure the states in a FlexBE state machine, using the user data and behavior variables.
- How to connect all the states in your FlexBE state machine to implement the desired behavior.

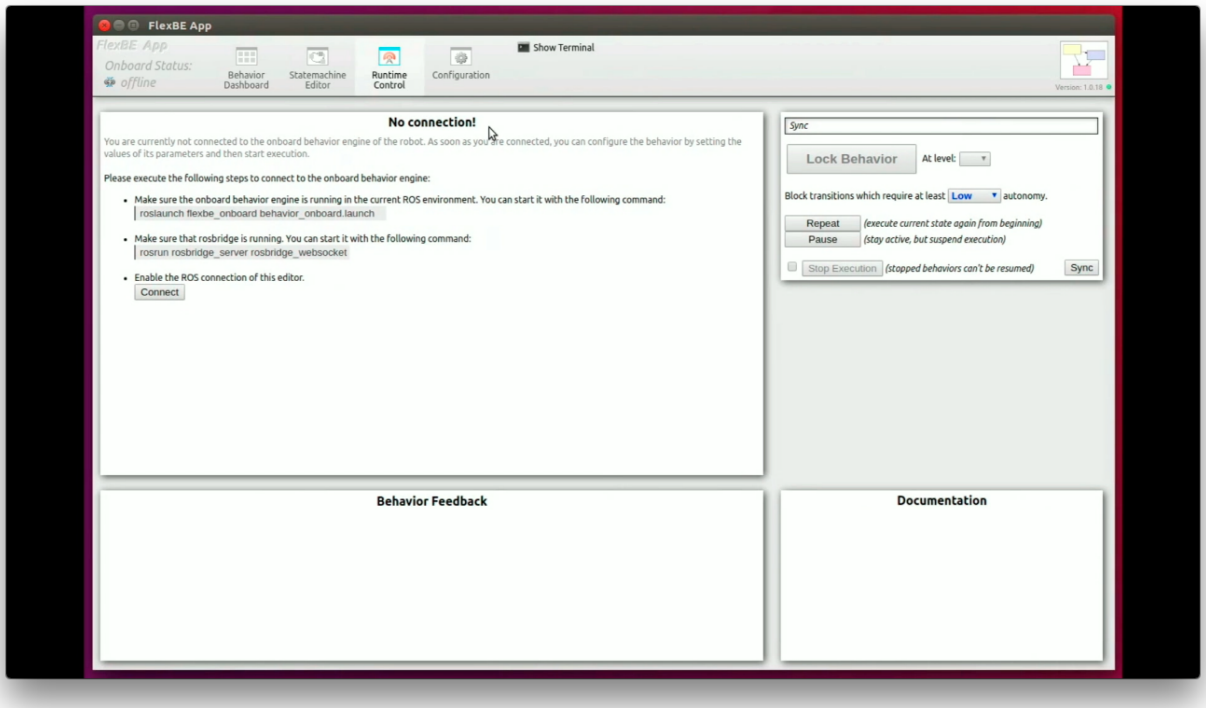
In this video you learned:

- How to execute your FlexBE behavior using the *Runtime Control* view
- That launching your ROS application and the whole FlexBE behavior engine are required steps to execute a behavior.
- That with FlexBE you can easily integrate robot behaviors in ROS. Our demo behavior successfully coordinated the ROS nodes to pick a part in our factory!

In the next unit you will learn what to do when there is no FlexBE state implementation available for one of the actions required in our behavior.

Important Note:
After installing the Week 6 files, you can execute the "*Pick part from conveyor*" behavior by following the instructions presented in the video. Remember that the state machine of the behavior included in the files is slightly different from the one shown in the videos, but the resulting behavior in the factory is the same.

Use this image to answer the question below



Question 1

1 point possible (ungraded)

What does the error message "No connection" shown in Figure A mean?

- There is no internet connection.
- The FlexBE behavior engine App is not connected to the FlexBE ROS node.
- The FlexBE App is not connected to the online state repositories.

Submit