Use the MoveIt MoveGroup Interface

The last assignment of this week requires you to implementing a simple pick and place pipeline for robot2. Using the same process as we did for robot1 in the Module 4.5

To achieve this, we will use a python script called `week4_assignment3.py` that sends commands to the robot2 using the `moveit_commander` API studied during the week. You can find this script in the `week4_assignment` package, included in the download files of this week.

For this assignment to work, you need to have completed Assignment 1, where you defined the robot poses that are going to be used here.

Week 4 - Assignment 3 --- 4 Points

To complete the last assignment of the week, you need to follow this steps.

Step 1: Complete the script `week4_assignment3.py` located on the scripts folder of the `hrwros_week4_assignment package.`

> **You only need to change wherever you are instructed with `<write your code here>`.**

Step 2: After you have completed the script, start the factory simulation in a new CCS with:

```
$ roslaunch hrwros_week4_assignment
hrwros_week4_environment.launch
```

Step 3: Make sure to adjust the perspective of the Gazebo Simulation to have a clear view of Robot2.

Step 4: In another CCS, first navigate to the `hrwros_week4_assignment/scripts` folder with `roscd and` Make sure the `week4_assignment3.py` script is executable.

Step 4: Finally, run the command:

```
$ roslaunch hrwros_week4_assignment
week4_assignment3.launch.
```

You should see the robot2 execute simple pick and place motions, in both RViz and Gazebo!!

This completes all the assignments for week 4.

You can now go to the submission unit of week 4, and upload your files.