

# Forward Kinematics Lead Through

1. Did you obtain the exact same default position for the end-effector at the start and end of a cycle when executing the Learn task? If the deviation between the start and end position was large, what could be the implications here when running the Follow task?
2. During the learning process, the operator must complete the motion in one go. Why does flipping the learn switch, taking a break, and then proceeding to work in practice?
3. Why does the lowest part of your trajectory need a 5 cm clearance w.r.t the table?
4. When you flipped the manual switch for **Filter?**, why did the performance change? What was filtered during this process?