

README: best

I used a feedforward PI controller to produce this trajectory. I chose $K_p = 1.75$ and $K_i = 1.5$.
The initial gripper-less configuration is
[$\pi/6$, 0, 0.2, 0, $\pi/3$, $-\pi/4$, $-\pi/2$, 0, 0, 0, 0, 0]