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README: newTask

I used a feedforward P controller to produce this trajectory. I chose Kp = 4.
The initial gripper-less configuration is
[pi/6, 0, 0.2, 0, pi/3, -pi/4, -pi/2, 0, 0, 0, 0, 0]

The initial position of the cube is at (1,1) with phi = pi/4.
The final position of the cube is at (1,-1) with phi = -pi/4.