

### PlaceClampToStructure (cid, jid)

#### RFL Robot - Free Motion

Bring **Clamp**(cid) to the first approach point of **Joint**(jid)

#### RFL Robot - Linear Motion

Move **Clamp**(cid) into second approach point of **Joint**(jid)

#### RFL Robot - Linear Motion

Move **Clamp**(cid) into hanging location of **Joint**(jid)

#### Clamp(cid) - Close Hangin Gripper

Lock clamp to the beam.

#### Operator - Inspection

Ensure clamp is hanging securely

#### Docking Adapter - Unlock Tool

Unlock **Clamp**(cid) from robot kinematic chain.

#### Robotic Arm - Linear Motion

Pull docking adapter away from tool.

### PickClampFromStructure(cid, jid)

#### RFL Robot - Free Motion

Bring **Docking Adapter** to approach the **Clamp**(cid) hanging at **Joint**(jid)

#### RFL Robot - Linear Motion

Insert docking adapter into tool-side of **Clamp**(cid).

#### Clamp(cid) - Open Hanging Gripper

Lock clamp to the joint.

#### Docking Adapter - Unlock Tool

Unlock **Clamp**(cid) from robot kinematic chain.

#### RFL Robot - Linear Motion

Move **Clamp**(cid) out of hanging position, step 1.

#### Operator - Inspection

Ensure clamp is free to move

#### RFL Robot - Linear Motion

Move **Clamp**(cid) out of hanging position, step 2.