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// Introduction DEMO
// Only works with v1 of the Dexter firmware
// Built off of Zach Arnold Demo code
function init_parameters(){

   Dexter.LINK4 = .0508 // 0.0508 (m)
   Dexter.LINK5 = 0.08255 // 0.08255 (m)

        return [
        make_ins("S", "MaxSpeed", 20),      // (deg/s)
        make_ins("S", "StartSpeed", .1),          // (deg/s)
        make_ins("S", "Acceleration", 0.000129), // (deg/s^2)
        make_ins("S", "J1BoundryHigh", 180),
        make_ins("S", "J1BoundryLow", -180),
        make_ins("S", "J2BoundryHigh", 90),
        make_ins("S", "J2BoundryLow", -90),
        make_ins("S", "J3BoundryHigh", 165),
        make_ins("S", "J3BoundryLow", -165),
        make_ins("S", "J4BoundryHigh", 100),
        make_ins("S", "J4BoundryLow", -100),

        make_ins("S", "J5BoundryHigh", 185),
        make_ins("S", "J5BoundryLow", -185),
                make_ins("S", "GripperMotor", 1),
       make_ins("w", 64, 80)
   ]
}

var pos1 = [0, 25, 140, -60, 0]
var pos2 = [-2, 36, 119, -60, 0]
var pos3 = [-2, 42, 112, -44, 0]
var pos4 = [10, 42, 113, -44, 0]
var pos5 = [-2, -20, 140, -90, 0]
var pos6 = [-160, -20, 140, -90, 0]
var pos7 = [-160, 0, 140, 0, 0]
var home = [0, 0, 0, 0, 0]

var pause = 1
var o = 180
var c = 98
//Home
new Job({name: "takeMeHome",
                do_list: [
                   init_parameters(),
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                    Dexter.move_all_joints(home)]})
//gripper Demo
new Job({name: "job_gripper",
      do_list: [
                        init_parameters(),
              Dexter.wait_until(pause), // pause
               // Gripper Demo remake
                // Close
              Dexter.move_all_joints(home),
              Dexter.set_parameter("EESpan", c),
              Dexter.move_all_joints(home),
              // Open
              Dexter.move_all_joints(home),
              Dexter.set_parameter("EESpan", o),
               Dexter.move_all_joints(home),
              Dexter.move_all_joints(pos1),
              Dexter.move_all_joints(pos2),
              Dexter.move_all_joints(pos3),
               Dexter.wait_until(pause), // pause
               Dexter.set_parameter("EESpan", c), // gripper
               Dexter.wait_until(pause), // pause
                Dexter.move_all_joints(pos3),
               Dexter.wait_until(pause), // pause
               Dexter.move_all_joints(pos4),
               Dexter.move_all_joints(pos3),
               Dexter.move_all_joints(pos5),
               Dexter.move_all_joints(pos6),
               Dexter.move_all_joints(pos7),
               Dexter.wait_until(pause), // pause
               Dexter.set_parameter("EESpan", o), // gripper open
               Dexter.wait_until(pause), // pause
               Dexter.move_all_joints(pos6),
               Dexter.move_all_joints(pos5),
               Dexter.move_all_joints(home)
             ]})

// Test
new Job({name: "test",
      do_list: [
      init_parameters(),
      Dexter.move_all_joints(home)
              ]})
```