WRITE UP OF STARTER CODE

1. The difference between motion_planning and backyard_flyer project is the PLANNING state in Enum states.
2. In Utils file search algorithm are defined in function and are imported in motion_planning code. Like A_star algorithm, collinearity check, prune path, grid creating are done.
3. The 'colliders.csv' is read in python script using open and read functions along with strip function to define the lat0, lon0 from .csv file.

```python
with open('colliders.csv' , 'r') as csv_file:
    csv_reader = csv.reader(csv_file)

    x = next(csv_reader)

    lat0 = float((x[0].strip('lat0')))
    lon0 = float((x[1].strip(' lon0')))
```

4. Using frame utils coordinate transformation is done using global_to_local function to define the local position of drone.

```python
local_position = global_to_local(global_position,self.global_home)
```