

# Homework\_2: Smooth Navigation Path Generation

---

## 1. Requirement

- The code framework is based on [GCOPTER](#), which is an efficient and versatile multi-copter trajectory optimizer.
- ROS should be installed in advance. Ubuntu 20.04 and ROS noetic are recommended.

## 2. Run

- Unzip and enter the folder.
- Execute the following terminal commands.

```
## you should source the ros setup in advance

cd catkin_ws/src
catkin_init_workspace

cd..
catkin_make

source devel/setup.bash

roslaunch gcopter curve_gen.cpp
```

## 3. Result

- optimizing the path after choosing two target positions





