Moveit trajectory planning

1. Usage environment

Motherboard: Jetson Orin Nano/Nx

ROS2: Humble

2. Driving the real machine

Driving the real machine is to convert the joint state information of the robot arm into the control of the real robot arm by subscribing to the `/joint_states` topic of Moveit2.

Note: Since the real robot arm does not have an obstacle avoidance function, some positions may hit obstacles; so the planned robot arm movements should be as reasonable as possible and avoid positions with obstacles

(It is recommended to use preset positions to demonstrate driving the real machine)

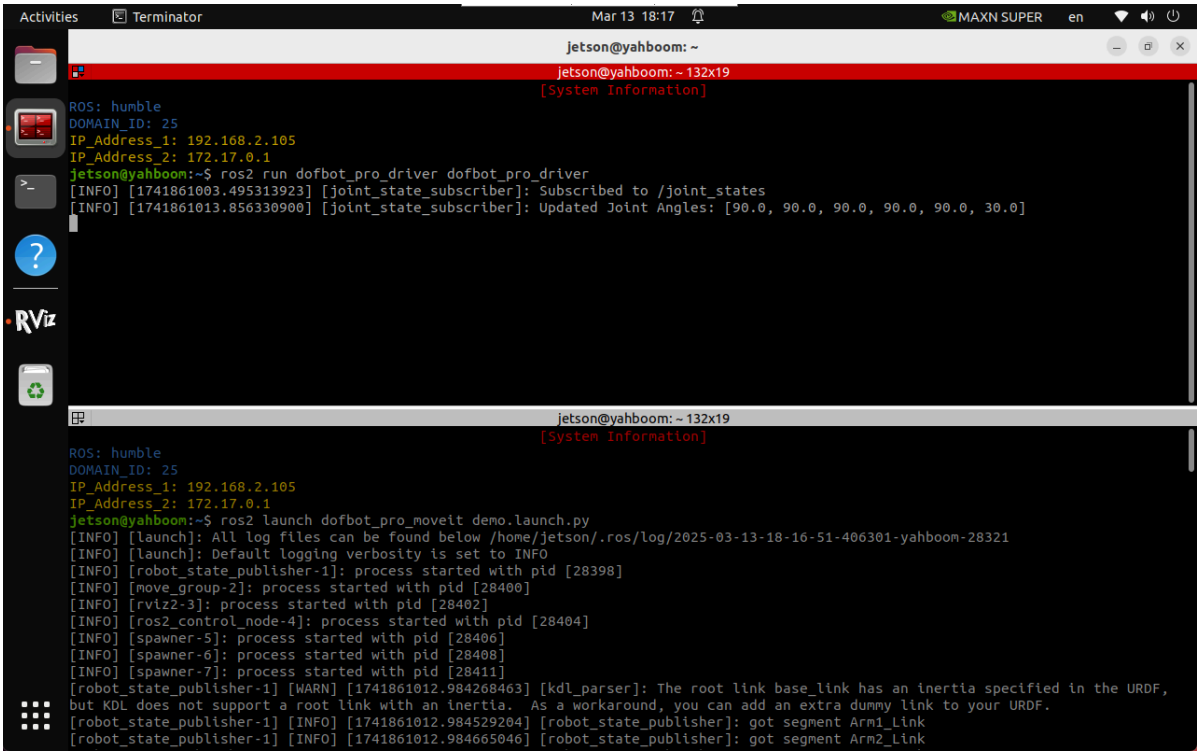
2.1. Start the real machine

If you do not drive the real machine, simulate the robot arm movements in MoveIt:

```
ros2 run dofbot_pro_driver dofbot_pro_driver
```

2.2. Start MoveIt2

```
ros2 launch dofbot_pro_moveit demo.launch.py
```

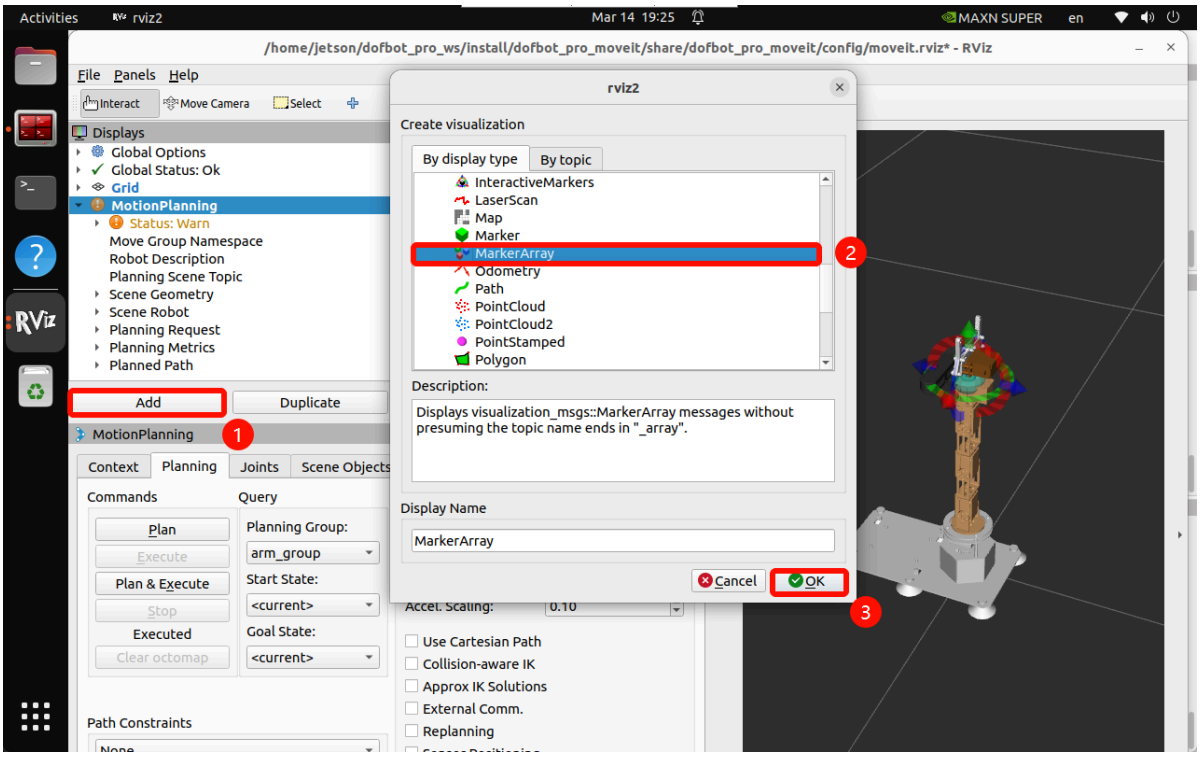


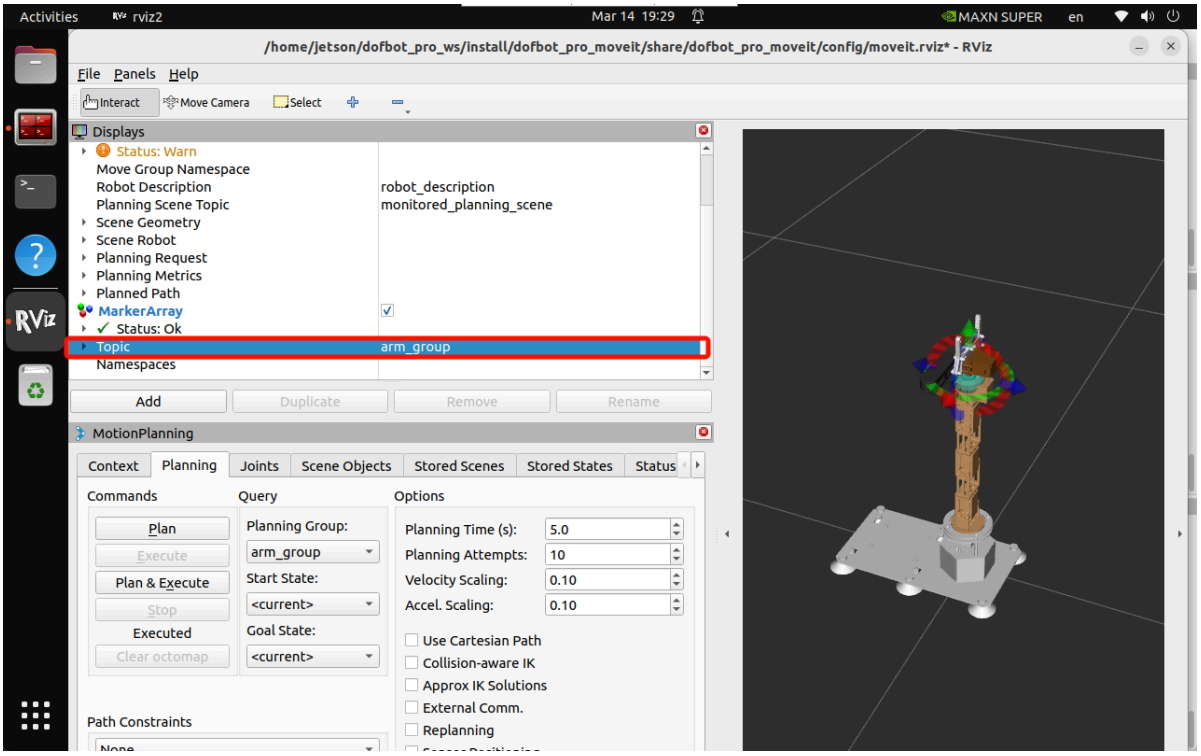
3. Trajectory planning

After the program runs, the robot arm will plan the trajectory of the target position, and the end effector of the robot arm will draw the motion trajectory in RViz2.

3.1, Visualization

Before starting the command, you need to add the `MarkerArray` plug-in in `RViz2` to display the planned path: `MarkerArray` needs to select the `arm_group` topic





3.2, Start Command

The robot needs to be successfully loaded in MoveIt and `You can start planning now!` appears to run the following command: The robot will automatically draw the trajectory of the planned path

```
ros2 run dofbot_pro_moveit multi_track_motion
```