Overview	**Implementation**
This Arm path planner can be used to move the arm end effector to desired. This can be used to automate menial tasks and to some extent replace human hands	Working on 3D cartesian coordinates. Implements Inverse Kinematics solver and path planner modules by MoveIT. In trajectory planning, STOMP optimization method is used .Simulates output using Coppeliasim
What's New	**Results**
Fast Implementation - 3 week single release delivery Inbuilt Forward kinematics solver to verify output Output simulated in a virtual environment	Timeline : 3 weeks Budget: Open source libraries used, no 3rd party licensing expense Deliverable: A package with Robotic arm path planner Testing : Forward Kinematics for verification and real-time simulation