$ sudo apt-get install ros-noetic-moveit-visual-tools

### $ sudo apt-get install ros-noetic-moveit-ros-visualization

**aswath@aswath-ROG-Zephyrus-G15-GA502IV**:**~**$ rostopic echo /waypoints

header:

seq: 1

stamp:

secs: 1616178132

nsecs: 505594243

frame\_id: "map"

joint\_names:

- Quadcopter

points:

-

transforms:

-

translation:

x: 1.0

y: 1.0

z: 1.0

rotation:

x: 0.0

y: 0.0

z: 0.0

w: 1.0

velocities: []

accelerations: []

time\_from\_start:

secs: 1616178132

nsecs: 505599976

-

transforms:

-

translation:

x: 12.153601012606858

y: -10.46767516414799

z: 8.052331359431108

rotation:

x: -0.2004621408389971

y: -0.09591581722189894

z: 0.14226734229783894

w: 0.9645595312951973

velocities: []

accelerations: []

time\_from\_start:

secs: 1616178132

nsecs: 505604982

-

2D path planning:

https://ompl.kavrakilab.org/optimalPlanningTutorial.html

