

1. At this point, the ROS package from the MoveIt setup document should be generated
2. Add the ROS package path to your ROS_PACKAGE_PATH environment variable with
 - a. Export ROS_PACKAGE_PATH="your/path/here":\$ROS_PACKAGE_PATH
3. Launch Rviz with
 - a. Roscore (run from a separate terminal)
 - b. Roslaunch /path/to/demo.launch
4. Add Motion Planning panel if not already present by
 - a. Click Add
 - b. Select MotionPlanning
5. Change Planning Scene Topic to /planning_scene
6. Under Scene Robot Under MotionPlanning
 - a. You can choose Show Robot Collision for collisions
7. Under Planning Request
 - a. You can enable Start or End State visualization
8. Under Planned Path
 - a. Click Show Robot Collision if you wish to show collisions
9. Make sure the Planning Library OMPL is loaded
 - a. If it does not show as loaded and all steps have worked up to this point, restarting the computer may help
10. Drag the arm to a position or choose a random position in the Planning tab under Query
11. Click Plan to see the path or Plan and Execute to actually execute the motion in simulation