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
   1. Export ROS\_PACKAGE\_PATH=”your/path/here”:$ROS\_PACKAGE\_PATH
3. Launch Rviz with
   1. Roscore (run from a separate terminal)
   2. Roslaunch /path/to/demo.launch
4. Add Motion Planning panel if not already present by
   1. Click Add
   2. Select MotionPlanning
5. Change Planning Scene Topic to /planning\_scene
6. Under Scene Robot Under MotionPlanning
   1. You can choose Show Robot Collision for collisions
7. Under Planning Request
   1. You can enable Start or End State visualization
8. Under Planned Path
   1. Click Show Robot Collision if you wish to show collisions
9. Make sure the Planning Library OMPL is loaded
   1. 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