I installed OMPL in Ubuntu 16.04 (all my research is in this OS hence the choice) and I had quite a few issues which took me a while to figure out so I am putting this together for future reference to others in case you encounter the same issues.

OMPL has a web app that you can use incase you don't need or want to install it locally in your computer: http://omplapp.kavrakilab.org/

To install locally:

1. http://ompl.kavrakilab.org/installation.html I downloaded the installation script from this link and followed the steps which are straight forward. I installed both the OMPL library and app with python bindings.
2. The python bindings require a lot of RAM and several times my computer would freeze without finishing installation. The make –j 1 update_bindings utilizes only 1 core which is why it took so long and kept freezing eventually causing incomplete installation

The installation script has these commands as part of it:

```
mkdir -p build/Release
cd build/Release
cmake ../.. -DPYTHON_EXEC=/usr/bin/python${PYTHONV}
if [ ! -z $PYTHON ]; then
    # Check if the total memory is less than 6GB.
    if [ `cat /proc/meminfo | head -1 | awk '{print $2}'` -lt 6291456 ]; then
        echo "Python binding generation is very memory intensive. At least 6GB of RAM is recommended."
        echo "Proceeding with binding generation using 1 core..."
        make -j 1 update_bindings
    else
        make update_bindings
    fi
fi
make
```

```
${SUDO} make install
}
```

3. Most of my issues were resolved when I followed these steps to enable complete installation:

Go to the ompl_app directory, in my case *omplapp-1.5.0-Source*

cd omplapp-1.5.0-Source/ build/Release

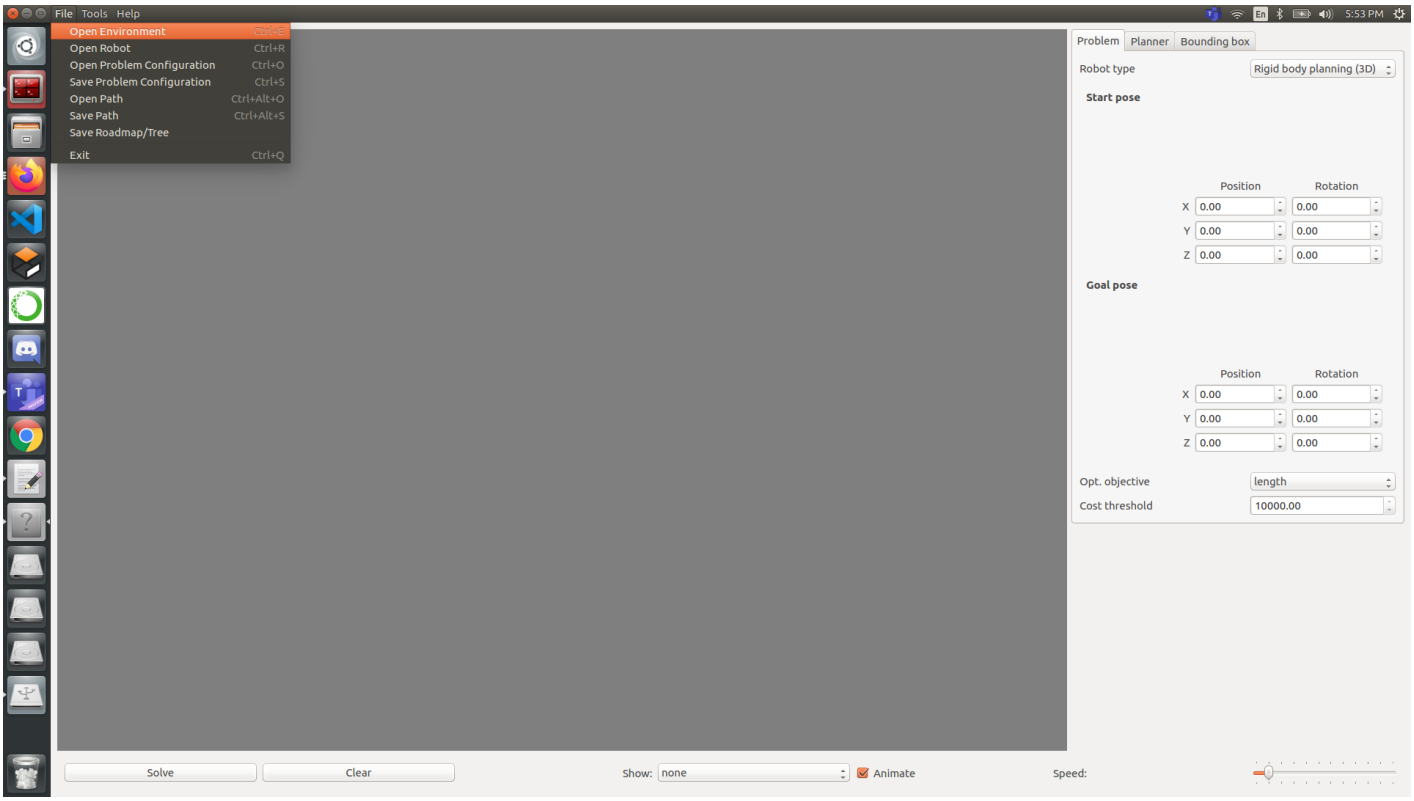
Then enter the following commands,

- *make -j 4 update_bindings* or *make –j 2 update_bindings* if your computer is dual core (for Python binding generation)
- Compile OMPL.app by typing *make -j 4*

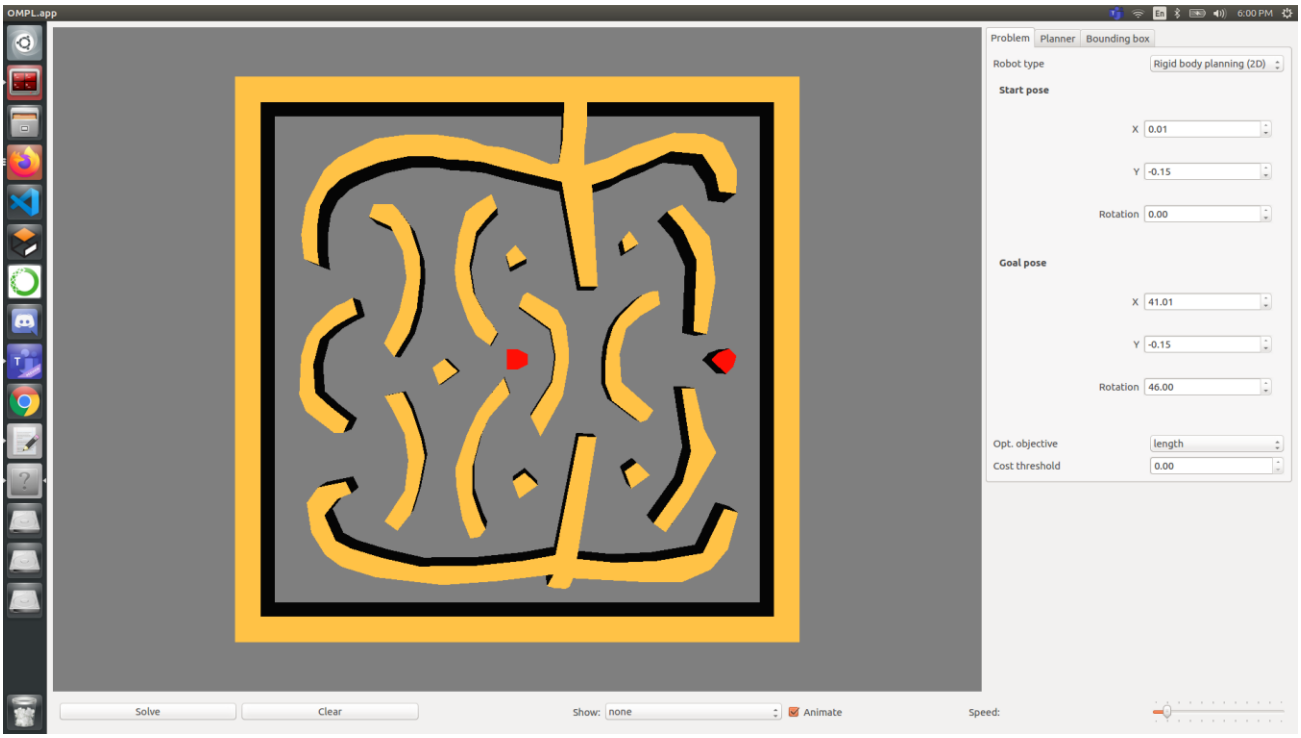
This should make sure the binding generation is complete

Now, you can launch ompl_app by typing *ompl_app* in the terminal window.

You would see this window popping up



You need to go to file and open a problem configuration like this one



From here you can go ahead add a robot of your choice and play around with the available motion planners.