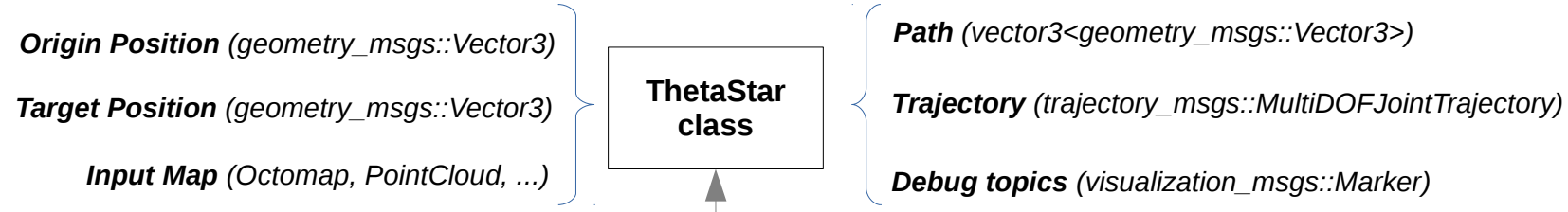
Weighted Lazy Theta* with Optmiz.



Configuration (parameters from launch)

- ***WorkSpace*** *[m]: [Xmax,Ymax, Zmax, Xmin, Ymin]. Centered at (0,0,0)*
- ***Map Resolution*** *[m]: Occupancy matrix step*
- ***Inflations*** *[m]: MAV Real size and Safe distances to the obstacles*
- ***TimeOut*** *[sec]: Max time to get a valid solution*
- ***Initial point factor*** *[]: Factor to decrease the weight to the distance from the origin, giving more importance to explore towards the goal*
- ***Altitude weight*** *[]: Weight to increase the cost of altitude changes*
- ***Min inflated altitude*** *[m]: Minimum altitude to inflate vertically (spurious at floor)*
- ***Result trajectory parameters*** *[m, m/s, rad/s]:*

$(Dxy, Dz)_{max}$ [m]:	Max distance between waypoints
$(Dxy, Dz)_{tol}$ [m]:	Tolerance to the waypoints distance
$(Vxy, Vz)_{avrg}$ [m/s]:	Mean velocity
$(Vxy, Vz)_{avrg\_if}$ [m/s]:	Initial and final wps mean velocity
$(Wyaw)_{avrg}$ [rad/s]:	Angular velocity
$(Dyaw)_{tol}$ [m]:	Min distance between wps to set yaw Ahead