waypoint.py :

Creates an object of move2goal waits for the rospy to shutdown.  
move2goal:

* s\_pose, d\_pose topics are created and subscribed to which are of Pose2D() type.
* an update of d\_pose triggers waypoint(s\_pose,d\_pose)
* the namespaces for each bot are created in the launch files

source.py :

fetches data from gazebo and publishes it to respective s\_pose for all the robots in the simulation  
note: this can be modified to launch in a specific namespace

destination\_robotX :

contains the destination coordinates as a list  
subscribes -> robotX/s\_pose  
publishes -> robotX/d\_pose

drifting is tolerated by sampling the path into smaller lengths of d\_sample.