

```
adilhusain@adilhusain-VirtualBox: ~  
adilhusain@adilhusain-VirtualBox:~$ dronekit-sitl copter --home=35.9835973,-95.8742309,0,90  
os: linux, apm: copter, release: stable  
SITL already Downloaded and Extracted.  
Ready to boot.  
Execute: /home/adilhusain/.dronekit/sitl/copter-3.3/apm --home=35.9835973,-95.8742309,0,90 --model=quad -I  
0  
SITL-0> Started model quad at 35.9835973,-95.8742309,0,90 at speed 1.0  
SITL-0.stderr> bind port 5760 for 0  
Starting sketch 'ArduCopter'  
Serial port 0 on TCP port 5760  
Starting SITL input  
Waiting for connection ....
```

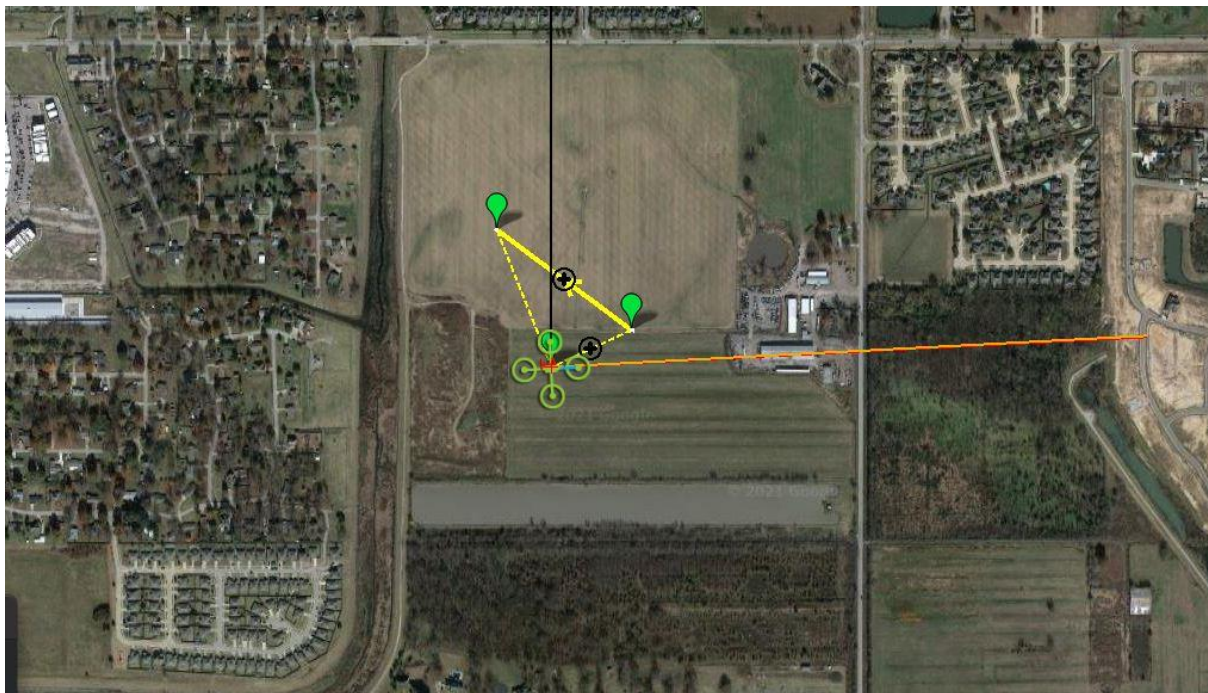
Drone simulator

```
adilhusain@adilhusain-VirtualBox: ~  
adilhusain@adilhusain-VirtualBox:~$ mavproxy.py --master tcp:127.0.0.1:5760 --out udp:127.0.0.1:14551 --ou  
t udp:10.55.222.120:14550  
Connect tcp:127.0.0.1:5760 source_system=255  
Log Directory:  
Telemetry log: mav.tlog  
Waiting for heartbeat from tcp:127.0.0.1:5760  
MAV> online system 1  
STABILIZE> Mode STABILIZE  
AP: Calibrating barometer  
AP: Initialising APM...  
AP: barometer calibration complete  
AP: GROUND START  
Init Gyro**  
INS  
-----  
G_off: 0.00, 0.00, 0.00  
A_off: 0.00, 0.00, 0.00  
A_scale: 1.00, 1.00, 1.00  
  
Ready to FLY ublox
```

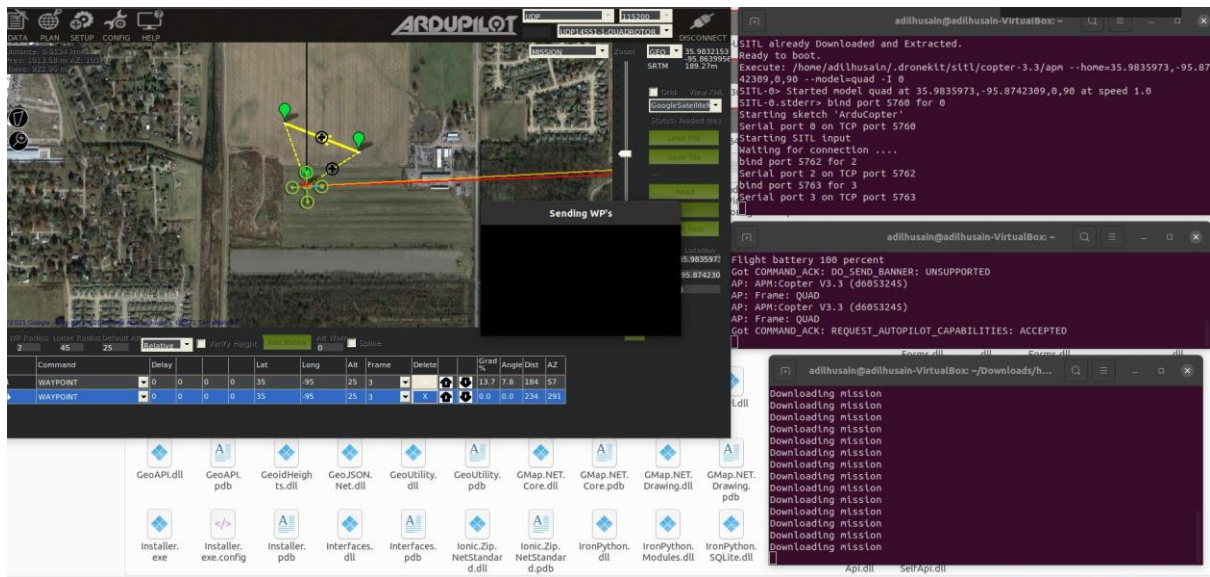
Start Mavproxy so we can connect both the Companion PC(where we have python script) and the mission planner(where we have drone).

```
adilhusain@adilhusain-VirtualBox: ~/Downloads/how_do_dr...
adilhusain@adilhusain-VirtualBox:~/Downloads/how_do_drones_work-master/scripts$
sudo python 04_mission.py
[sudo] password for adilhusain:
Connecting...
CRITICAL:autopilot:APM:Copter V3.3 (d6053245)
CRITICAL:autopilot:Frame: QUAD
Downloading mission
Downloading mission
Downloading mission
Downloading mission
```

Running python script to download the mission in our drone



After downloading mission we can allot the waypoints to our drone so it can have to follow the particular path to complete the mission.



Whole process in this screenshot.