**How to set up SITL**

1. Install Pyhton 2.7 ( Python 3 is not supported)
2. Install dronekit package in python

(python –m pip install dronekit)

1. Install dronekit-sitl package in python

(python –m pip install dronekit-sitl)

1. Install Mission Planner from:

<http://ardupilot.org/planner/docs/common-install-mission-planner.html>

or APMPlanner2 for linux

1. Install Mavproxy (version 1.5.2 !!! It’s important! – for linux no difference) from:

<http://firmware.eu.ardupilot.org/Tools/MAVProxy/>

1. Install wxPython from – not needed in Linux:

[https://wxpython.org/download.php#msw](https://wxpython.org/download.php%23msw)

1. Install wx\_phoenix package in Python from – not needed in Linux:

<https://wxpython.org/Phoenix/snapshot-builds/>

(python –m pip install filename.whl)

Install MAVproxy package in Python

(python –m pip install mavproxy==1.5.2)

1. Install numpy package in Python
2. Install openCV package in Python – not needed in Linux

(I don’t know why, but just do it, because without opencv it doesn’t work)

1. Run SITL: tape in cmd : dronekit-sitl copter-3.3
2. Run mavproxy:

C:\Program Files (x86)\MAVProxy\mavproxy.exe --master tcp:127.0.0.1:5760 --out udpout:127.0.0.1:14550

--master connect to vehicle ( 5760,5763…(+3))

--out port for other connection(14550,14552…(+2))

(make new “out” port for dronekit connection if you want to control from computer)

12. Run Mision Planner:

Choose upd , then tape 14550, press connect.

13.You can control vehicle by mavproxy cmd:

mode guided

arm throttle

take off 100

Vehicle will take off.

DONE!!!