Go_to:
http://www.ros.org/wiki/ROS/Installation
--follow ROS installation instructions for ubuntu-
Mandatory:
Full ROS Installation (groovy Galapagos distribution):

```
--update the system
sudo apt-get update
-- install ROS:
sudo apt-get install ros-groovy-desktop-full
--initilize rosdep:
sudo rosdep init
rosdep update
--Environment setup:
echo "source /opt/ros/groovy/setup.bash" >> ~/.bashrc
source ~/.bashrc
source /opt/ros/groovy/setup.bash
--get rosinstall:
sudo apt-get install python-rosinstall
```

Installation_of_ar.drone_autonomy_driver

1. Open terminal.
2. change to super-user:

```
sudo -s
```

3. go to:

```
cd ~/.ros/
```

4. Clone ardrone_autonomy repository

```
git clone git://github.com/tum-vision/ardrone_autonomy.git
ardrone_autonomy
```

5.add to path

```
export ROS_PACKAGE_PATH=$ROS_PACKAGE_PATH:`pwd`/
ardrone_autonomy
```

6. type:

```
roscd ardrone_autonomy
```

7. now in ~/.ros/ardrone_autonomy, build SDK:

```
./build_sdk.sh
```

8.build package (take few minutes)

```
rosmake
```

RUN driver for ar.drone connection:

1. connect to ar.drone wifi network

2. go to:
~.ros/ardrone_autonomy/launch

3. run driver
roslaunch ardrone_autonomy ardrone.launch

4. open new console and see topic options of node:
rostopic list

5. echo to one of the topic options: for e.g the IMU data:
rostopic echo /ardrone/imu

---- Tum_ardrone

1.launch tum_ardrone for running algorithms: control, estimation, GUI

roslaunch tum_ardrone tum_ardrone.launch