Guaranteed to work on Ubuntu 18 only

1. Install ROS melodic
2. Install Gazebo **9.16**
3. Create workspace
    a. **mkdir far_ws**
    b. Inside /far_ws: **mkdir src**
4. Clone Payam's *follow_ahead_rl* git repo into **src**
5. Clone multi_jackal into **src**
6. Download dependencies
    a. **sudo apt install ros-melodic-turtlebot3-description ros-melodic-control-msgs ros-melodic-control-toolbox ros-melodic-controller-interface ros-melodic-controller-manager ros-melodic-controller-manager-msgs ros-melodic-diff-drive-controller ros-melodic-forward-command-controller ros-melodic-gazebo-ros-control ros-melodic-joint-state-controller ros-melodic-position-controllers ros-melodic-robot-localization ros-melodic-move-base ros-melodic-lms1xx ros-melodic-pointgrey-camera-driver ros-melodic-pointgrey-camera-description ros-melodic-hector-gazebo-plugins ros-melodic-interactive-marker-twist-server**
7. Build project:
    a. Go back to **/far_ws** directory
    b. Run **catkin_make**
8. Source workspace: ***source devel/setup.bash***
9. **roslaunch src/follow_ahead_rl/launch/turtlebot.launch**

ROS Dependencies
turtlebot3-description
control-msgs
control-toolbox
controller-interface
controller-manager
controller-manager-msgs
diff-drive-controller
forward-command-controller
gazebo-ros-control
joint-state-controller
position-controllers

Multi_Jackal dependencies
robot-localization
move-base
lms1xx
pointgrey-camera-driver
pointgrey-camera-description
hector-gazebo-plugins
interactive-marker-twist-server

Navigation/ Gym Env
global-planner
teb-local-planner
move-base
costmap-converter

Python Dependencies
Ppo_continuous dependencies:
tensorboardX
simple-pid
ipython

D4pg dependencies:
pandas
seaborn