Installing edrone Packages on Ubuntu 16.04

Installation instructions:

This document assumes that the host OS on which our packages is to be installed is **Ubuntu 16.04 LTS**. Follow the guidelines.

- First we install some Linux libraries (Package dependency) that our ROS package depends upon, to do so, we run the following commands:

```
> sudo apt-get install git

> sudo apt install libavcodec-dev libsdl2-dev xsltproc \
libbullet-dev libsdl1.2-dev libgoogle-glog-dev \
protobuf-compiler python-wstool python-catkin-tools

> sudo apt-get install gazebo7 libgazebo7-*

> sudo apt-get install ros-kinetic-tf-*

> sudo apt-get install ros-kinetic-pcl-msgs \
ros-kinetic-mav-msgs ros-kinetic-mavros ros-kinetic-octomap-* \
ros-kinetic-geographic-msgs libgeographic-dev
```

- Change the directory to your catkin workspace and clone these GitHub repositories in "src" folder of workspace by typing the following commands:

```
> cd ~/catkin_ws/src

> git clone https://github.com/ros/geometry2.git

> git clone https://github.com/wnowak/brics_actuator.git

> git clone https://github.com/simmubhangu/eyantra_drone.git

> git clone https://github.com/lrse/whycon.git
```

- Change directory to your catkin workspace and run command catkin_make

```
> cd ..
```

Or by entering

```
> cd ~/catkin_ws
```

Now, after successfully adding the packages into our ***src*** folder, lets build them, by executing the following command..

```
>     catkin_make
```

This will build any packages in the source space (~/catkin_ws/src) to the build space(~/catkin_ws/build). Any source files, python libraries, scripts or any other static files will remain in the source space. However, any generated files such as libraries, executable, or generated code will be placed in the devel space. Also in the devel space there will be setup.*sh files generated (we'll be using *setup.bash)*, which when sourced will prefix your environment with this devel space.To do so, just enter following command ..

```
>     source devel/setup.bash
```