

PX4+路径规划仿真环境配置

配置可以用于仿真的PX4，直接用我仓库里的：

```
1 git clone https://github.com/BambiplayGit/PX4-Autopilot.git
2 make px4_sitl gazebo
```

bashrc里添加这些

```
1 source /home/yujc/PX4-Autopilot/Tools/setup_gazebo.bash /home/yujc/PX4-Autopilot/
2 export ROS_PACKAGE_PATH=$ROS_PACKAGE_PATH:/home/yujc/PX4-Autopilot
3 export ROS_PACKAGE_PATH=$ROS_PACKAGE_PATH:/home/yujc/PX4-Autopilot/Tools/sitl_gazebo
```

配置无人机工作空间

安装修改过的

```
1 git clone https://github.com/BambiplayGit/BambiplayGit-Fast-Drone-250.git -b tuned
2 cd PX4-Autopilot
```

安装ceres与glog与ddynamic-reconfigure

- 解压 3rd_party.zip 压缩包
- 进入glog文件夹打开终端
- `./autogen.sh && ./configure && make && sudo make install`
- `sudo apt-get install liblapack-dev libsuitesparse-dev libcxsparse3.1.2 libgflags-dev libgoogle-glog-dev libgtest-dev`
- 进入ceres文件夹打开终端
- `mkdir build`
- `cd build`
- `cmake ..`

- `sudo make -j4`
- `sudo make install`
- `sudo apt-get install ros-noetic-ddynamic-reconfigure`

编译

```
1 cd ~/Fast250
2 catkin_make
```

Quick Start

```
1 . Fast250/shfiles/autosim.sh
```

有一些绝对路径要修改一下