Programme	:	**B.TECH**	Semester	:	**WIN-22-23**
Course	:	**Drone Applications, Components and Assembly**	Code	:	**CSE2040**
Faculty	:	**Dr Muthu Manikandad**	Slot	:	**L43+L44**

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Ex. No. 4

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LAB-4:

To make the PX4 simulator run in different world, there a certain steps to be followed:

- First we need to go to the firmware folder

- Then go to the terminal from that location

- Type the following command in the terminal **"make px4_sitl_default Gazebo_iris__warehouse"**

These steps will help us to create a world in the Gazebo with the iris quadrotor model and in the warehouse world.

Here are the screenshots that have been taken during the execution.


```
INFO  [logger] Start file log (type: full)
INFO  [logger] [logger] ./log/2023-03-06/14_14_56.ulg
INFO  [logger] Opened full log file: ./log/2023-03-06/14_14_56.ulg
INFO  [mavlink] MAVLink only on localhost (set param MAV_{i}_BROADCAST = 1 to en
able network)
INFO  [mavlink] MAVLink only on localhost (set param MAV_{i}_BROADCAST = 1 to en
able network)
INFO  [px4] Startup script returned successfully
pxh>
pxh> INFO  [health_and_arming_checks] Preflight Fail: No manual control input
INFO  [tone_alarm] home set
INFO  [health_and_arming_checks] Preflight Fail: No manual control input
INFO  [health_and_arming_checks] Preflight Fail: No manual control input
INFO  [commander] Ready for takeoff!
INFO  [health_and_arming_checks] Preflight Fail: No manual control input
pxh> command[Wrn] [Publisher.cc:135] Queue limit reached for topic /gazebo/defau
lt/user_camera/pose, deleting message. This warning is printed only once.
pxh> commander takeoff
pxh> INFO  [commander] Armed by internal command
INFO  [tone_alarm] arming warning
INFO  [navigator] Using minimum takeoff altitude: 2.50 m
INFO  [health_and_arming_checks] Preflight Fail: No manual control input
INFO  [commander] Takeoff detected
```