# PX4<>Gazebo Dokumentation:

## Adding new aircraft/drone model:

* Create a folder under PX4-Autopilot/Tools/sitl\_gazebo/models for my model, named my\_vehicle
* Create the following files under PX4-Autopilot/Tools/sitl\_gazebo/models/my\_vehicle: model.config and my\_vehicle.sdf (these can be based off the iris or solo models in Tools/sitl\_gazebo/models)
* Create my own airframe file PX4-Autopilot/ROMFS/px4fmu\_common/init.d-posix/airframes

Adding default parameters inclusive Mixer settings

* Add the airframe name to PX4-Autopilot/ROMFS/px4fmu\_common/init.d-posix/airframes/CMakeLists.txt
* Create a file with the name of the new airframe in PX4-Autopilot/build/px4\_sitl\_default/etc/init.d-posix/airframes   
  The file could be empty. All the settings will be written during build of PX4 from the file located under PX4-Autopilot/ROMFS/px4fmu\_common/init.d-posix/airframes
* Add the airframe name to the platforms/posix/cmake/sitl\_target.cmake in the command set(models …)