

To run zephyr on Gazebo, SITL, QGroundControl

After installation gazebo, ardupilot_gazebo and ardupilot folders and requirements

Open terminal

`gazebo --verbose <zephyr.world address>`

example

`gazebo --verbose '/home/halit/ardupilot_gazebo/worlds/zephyr_ardupilot_demo.world'`

open another terminal

`cd ardupilot/ArduPlane`

`sim_vehicle.py -v ArduPlane -f gazebo-zephyr --console`

open QGroundControl

QGC and SITL are connected directly, but in QGC, not ready to fly.

In SITL terminal

`disarm`

`mode loiter`

in QGC

click yellow area in left top corner next to QGC logo

click arm

scroll button in bottom

draw mission in fly

upload

click action

click continuous mission