

# Guideline To operate drone

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## Guidelines and important information:

- make sure that any other student is not connected to drone's wifi
- connect to drone wifi
- Then source your workspace and open At least 3 terminal :
  - 1st terminal : “for bebop driver” command : `roslaunch bebop_driver bebop_with_vel_controller.launch`
  - 2nd terminal : ” to interact with opti track system ” command : `roslaunch vrpn_client_ros sample.launch server:=192.168.1.134`
  - 3rd terminal : ” take off ” . command : `rostopic pub /bebop/takeoff std_msgs/Empty “{}”`
  - 4th terminal **important** : ” for emergency landing ” bebop landing command : `rostopic pub /bebop/land std_msgs/Empty “{}”`
- you may use the 4th command for emergency landing .
- if you get the following error while launching your ros application :
  - `roscore cannot run as another roscore/master is already running & Please kill other roscore/master processes before relaunching.`
- consider using following commands to properly close the previous ros application/server :
- after you stop the previous ros application by `ctrl+c` you may do:
- `killall -9 roscore`
- `killall -9 rosmaster`
- `killall -9 gzserver`
- To work with optitrack system you need connect to the opti-track router via ethernet
- you may consider using `tmux` ( recommended)
- link to install : terminator
- tips to use terminator tips