Installing V-REP ROS Interface Package on Ubuntu 16.04

This file will help you to install the ROS package required to enable communication between your ROS nodes and the simulator. It is named the V-REP ROS Interface.

Installing instructions:

This document assumes that the host OS on which V-REP is to be installed is **Ubuntu 16.04 LTS**. Follow the guidelines to run V-REP:

• First we install some Linux packages that our ROS package depends upon, to do so, we run the following command:

```
>> sudo apt install xsltproc libbullet-dev
```

• Change the directory to your catkin workspace and clone these GitHub repositories in "src" folder of workspace by typing the following commands:

```
>> cd ~/catkin_ws/src
>> git clone https://github.com/ros/geometry2.git
>> git clone https://github.com/wnowak/brics_actuator.git
>> git clone https://github.com/fayyazpocker/vrep_ros_interface
>> git clone https://github.com/simmubhangu/pluto_drone
```

• In your terminal type the following command:

```
>> printf "\nsource ~/catkin_ws/devel/setup.bash
        export VREP_ROOT=~/V-REP_PRO_EDU_V3_5_0_Linux" >> ~/.bashrc
```

• The above command assumes that you have copied the folder "**V-REP_PRO_EDU_V3_5_0_Linux"** in the **home** directory. If not either provide the path i.e. VREP_ROOT accordingly or copy the folder to home directory.

• To initialize the shell session, type the following command in your terminal

```
>> source ~/.bashrc
```

• Change directory to your catkin workspace and run command catkin_make

```
>> cd ..
>> catkin_make
```

• In order to copy the new .so file generated, open the vrep_ros_interface package in src directory and type ./install.sh

```
>> cd src/vrep_ros_interface
>> ./install.sh
```