**T1**: roslaunch imp\_wrlds step.launch **or** roslaunch imp\_wrlds sloppy.launch

**T2**: ../Tools/autotest/sim\_vehicle.py -f gazebo-iris

**T3**: roslaunch apm.launch

**->**

**>** Used plugin: RQT Multiplot

Download: sudo apt install ros-melodic-rqt-multiplot

**>** Running multiplot:

| In 4th terminal:

rosrun rqt\_multiplot rqt\_multiplot

**>** In the multiplot window, open the **terrain\_drone.xml or slope.xml** file that I added in the package.

**>** Then simply click on the run button on the top right corner of the plotting area.

**>** Then the terrain will be plotted and as the drone is commanded to move, it’s pose will also be plotted.

………………………………

**Python file:** scripts/terrain.py **&** scripts/slope.py (already added in the world launch file, not required to run separately)