

IMAV 2017 Virtual Challenge Guide

1. Introduction

A simulation environment was created to represent the IMAV 2017 indoor challenge to speed up the development process of the drone Navigation, Guidance and Control algorithms developed by the teams. This guide provides some help on how to set up and use the tools.

The simulation is built on ROS packages developed by the Technische Universität Darmstadt (repository [here](#)) and the Technical University of Munich (repository [here](#)).

2. Environment setup

a) Operating System

The simulation requires a Linux environment (latest Ubuntu is recommended, tested with 16.04.1). It can be a virtual system on a Windows host system, but please note that the recommended virtualization environment is VMware, because Hyper-V and VirtualBox does not perform well enough for the 3D simulation and visualization.

b) ROS, Gazebo, Repository

Run setup.sh by:

```
chmod +x setup.sh
./setup.sh
```

It will ask for your password because of the sudo.

c) Simulink

To connect to the ROS network on the virtual machine or on an external PC from MATLAB/Simulink, please refer our [documentation](#).

d) Notes

There is an OpenGL issue with VMware. If Gazebo crashes with the message:

```
VMware: vmw_ioctl_command error Invalid argument.
```

Then execute:

```
echo "export SVGA_VGPU10=0" >> ~/.bashrc
```

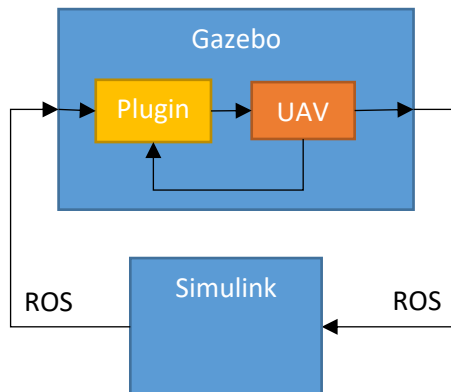
This changes the environment variable to use an earlier version of OpenGL. More info [here](#).

Also, there is a bug in gazebo_ros_pkgs, which makes the simulation crash if you try to remove a camera object from the scene. More info [here](#). You can pull the latest ros-simulation:kinetic-devel branch and build from source, or wait until they roll it out to the release branch. Please note that

this does not cause issues during the simulation, only when you try to remove (or respawn) the drone.

3. Simulation

The simulation represents the indoor challenge at IMAV 2017. Gazebo handles the physics of the rigid body (UAV), while the attached plugins take care of the sensor readings and stabilization of the system. The IMU data is used directly from the simulation in the inner loop (without noise), and the forces and torques are exerted on the body mimicking the effect of the propellers.



The outer loop (involving Simulink) handles the high-level planning based on the image and sensor data acquired by the virtual instruments. This is done through ROS by subscribing the corresponding topics, and publishing the velocity commands.

a) Launching the simulation

The simulation can be run by

```
roslaunch imav_2017 imav_indoor.launch
```

The robots can be spawned by:

```
cd ~catkin_ws/src/IMAV_2017_Virtual_Challenge/urdf
./spawnrobot.sh 1
```

You can spawn multiple drones by changing the ID (the argument of script).

To remove a drone from the simulation run:

```
rosservice call gazebo/delete_model '{model_name: quadrotor_[ID]}'
```

Please note that in the current gazebo_ros_pkgs release this will crash the simulation (see Notes above).

b) Controlling the drone from Simulink