Rover on the lander:

* Test cameras
* Test ptu for navcam
* Test localization sensors and components individually:  
  imu, visodom, slam, mapping, wheels encoders
* Test localization drift when stationary
* Test mapping aiming at the rover/lander and compare it with known models
* Test wheels deployment motors:  
  deploy wheels and check increase in elevation and correct orientation with imu (change in roll and pitch may indicate a problem in one or more wheels)
* Test wheels motors:  
  very short traverse, check wheels rotation visually with navcam and rover position with VO
* Test turning motors:  
  turn the wheels and check wheels rotation with rover navcam where possible (solar panels might be in the way) and landers cam if available
* Test Point turn:  
  check orientation with imu
* Test short traverse:  
  check localization wheel odometry (assume slip ratio to be 0 on the lander?)

Rover descending on the ramps:

* Test short traverse on the ramps

Rover on the ground near the lander:

* Test short traverse compare localization with lander cameras
* Perform a complete point turn to check localization and also visual inspection of the rover with lander cameras
* Test an Ackermann turn
* Manually identify obstacles and test the obstacle detection
* Test then obstacle avoidance

List of equipment to be commissioned:

* ADE: Actuator Drive Electronics
* BEMA: Bogie Electro-Mechanical Assembly
* LocCam
* NavCam
* PTU
* IMU
* Sun sensor
* Software:
  + Visual Odometry
  + Mapping
  + Wheel Odometry
  + Hazard Detector