**ROVER ON THE LANDER**

* Test cameras (navcam, loccam hazcam)
* Test ptu for navcam
* Test localization sensors and components individually  
  imu, visodom, slam, mapping
* Test localization drift when still
* Test mapping aiming at the rover/lander
* 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 rotation visually with navcam and maybe rover position with

imu and cameras

* 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 with imu and wheel odometry (assume slip ration 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 hackermann turn
* Manually identify obstacles and test the obstacle detection
* Test then obstacle avoidance

**GENERAL QUESTIONS:**

The lander has camera pointing inside?

As a rover should I assume exomars or a generic rover?