**Test Objective/Description:** Obstacle Map

**Location:** Fleming Lab

**Date:**

**Hardware Needed:** Drone, Guidance sensor, map of test area, obstacles

**Procedure:**

Place several obstacles in the flight space

On initialization, the drone is localized against the a priori map through human selection.

As the drone moves about the test space, the obstacle is pushed to the 2D map which is used by the Planning subsystem

The 2D map data product is analyzed to determine if the updates pushed by the mapping system correspond to real-world obstacles.

Accuracy is determined by measuring error between real-world location and estimated location

**Requirements Met**

|  |  |
| --- | --- |
| **7.3.1** |  |
|  |  |
|  |  |
|  |  |

**Test Anomalies**

|  |  |
| --- | --- |
|  |  |
|  |  |
|  |  |
|  |  |

**Test Results:**