**Test Objective/Description:** Using mapping data obtained by RTABMap, update a 2D map suitable for planning purposes with obstacles in a static setting

**Location:** Fleming Lab

**Date:**

**Hardware Needed:** Drone, Guidance, Obstacles, map of test space

**Procedure:**

Place obstacles in the test space.

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

Place an obstacle in the filed of view whenever the software pipeline is started.

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**

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| **7.2.1** |  |
| **7.2.2** |  |
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**Test Anomalies**

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**Test Results:**