

The test platform consists of the designated hardware, [*MinSeg M2V3 two-wheeled robot*, see Section ??], and the designated development PC, [see Section ??]. To interface with the hardware, a Simulink model and a hierarchy of Matlab subscripts were created.

The Simulink model is capable of:

- Acting as an algorithm with which to program the hardware, such that it may:
 - Process
 - Actuate
 - Communicate
- Simulate an equivalent model of "the hardware when loaded with the same algorithm".

The Matlab script hierarchy is capable of:

- Initialize model parameters.
- Reconfigure model subsystems.
- Initialize a build or simulate event.
- Initialize a read or write event.
- Post-process raw read data.
- Save processed read data as well as other configuration data.
- Plot processed read data.