

We were able to successfully modify the Parrot AR Drone 2.0 so that it would follow a RaspberryPi attached to the Leader drone. Some of our tests were slightly inaccurate. The drone's calculation to find the drone was consistently accurate in our test runs; it was the Follower drone's heading that was inaccurate. With this we determined that the inaccuracies were due to our Follower drone's compass as it had conflicting cardinal directions from an actual compass we compared it with. Wind also was a major factor, as it would alter the flight path of our drone.

Our GUI was nearly complete, however, there were issues with the speed at which our GUI would update with the actual test run. This resulted in our GUI to be very unresponsive. Since the GUI was being unresponsive, we conducted our tests by examining the printed console data.