Level of manual control that should be implemented

* Because it is a multi-robot system, each robot should have the capabilities to operate autonomously
* Because the final intent of the system is to explore remote unknown locations, the entire system should operate without human control

Initialization of the system

* All robots will start at the same central location with the computer

Level of environmental instrumentation

* The system is inspecting unexplored so no instrumentation is possible
* A single stationary bot is used for processing and localization

Sensing modes for localization

* 3D depth camera is our primary method of localization
* 2D LiDAR will be used to support the camera

Schemes for decision making and map processing

* Immediate processing and exploration tasks will run on individual platforms
* Merging of maps and group decision making (where to travel, when the map is complete, etc.) will occur on the off-board computer

Hierarchy of robot team

* All robots complete the same tasks (3D mapping) and send information to the common computer for processing