The goal of this project is to implement an auto recovery system for a ground launched drone. With the increasing use of drones in Search and Rescue (SAR) operations the ability to deploy the drone in a rapid manner is vital with launching them from a ground-based launcher being a popular option. During this project the drone should be able to detect when it is launched and auto-initiate a recovery sequence that sees the drone enter a stable hover at a user specified height. A GUI will be implemented from where the operator can specify the recover height, initiate the auto detection features on the drone, and observe the path of the drone. A successful implementation would see the drone auto-recover and enter a stable hover. Time permitting we hope to implement a system that is able to handle the drone being launched in any orientation allowing us to account fo ra scenario where the launcher behaves in an off-nominal state.