

1: Use a normal camera starting at a high position, showing the entire demo field setting, then gradually dive down into the pipe for a short go through to see how the pipe inside looks like.

2: Take a 360 round view of our robot. With some pop up labels pointing to the robot components

- Either the virtual 3D model or the physical one

3: Restart from the entrance of the pipe with the robot ready at the start line.

4: Switch to a screen capture of our GUI monitoring robot's view, along with a window recording how we are controlling the robot in reality

- Small window in bottom right hand corner featuring the controller

5: When we see a damage in the pipe, we circle it highlighting it in the video

- Zoom in on video feed so it becomes the focal point to identify the problem area
- Show it being logged in the map

6: Continue until we go through the entire pipe, and then return

Software: DaVinci Resolve