1. Drive forward until x distance from wall
2. Turn to parallel to wall
3. Drive forward until either
   1. New obstacle in front of robot
      1. Turn parallel to new obstacle at x from wall
   2. Wall being track along disappears
      1. Drive to end of current wall, then slightly further
      2. Turn until new wall is found
      3. Generate waypoint to be x from new wall
      4. Drive along new wall
4. When the robot has completed a full loop
   1. Determine if outer walls of room
      1. If yes Calculate interior area to be mapped
   2. turn perpendicular to wall
5. Drive forward until obstacle is found
   1. If previously mapped obstacle
      1. Travel along obstacle certain distance, turn away and search for new obstacle
   2. If new obstacle map as shown above
6. When entire interior area has been explored, terminate.