Project 1: Search and Sample Return

Vishnu Karpuram

Notebook Analysis

1. Describe in your writeup (and identify where in your code) how you modified or added functions to add obstacle and rock sample identification.

In order to implement obstacle and rock sample identification,

1. Describe in your writeup how you modified the process\_image() to demonstrate your analysis and how you created a worldmap. Include your video output with your submission.

Autonomous Navigation and Mapping

1. perception\_step() and decision\_step() functions have been filled in and their functionality explained in the writeup.
2. By running drive\_rover.pyand launching the simulator in autonomous mode, your rover does a reasonably good job at mapping the environment.
3. Note: running the simulator with different choices of resolution and graphics quality may produce different results, particularly on different machines! Make a note of your simulator settings (resolution and graphics quality set on launch) and frames per second (FPS output to terminal by drive\_rover.py) in your writeup when you submit the project so your reviewer can reproduce your results.