

1	Author	Robot	Use case	Sensing	Expl. Planning	Navigation	Comm.	Notes
	C23 Wulbrecher	Wheeled	Rescue	LiDAR	Frontier (optm. for turns)	?	?	\$6
	C23 Kulkarni	Legged, Aerial	Subterranean	LiDAR	Graph	?	Mesh	\$44
	C23 Traverso	Legged, Aerial	Subterranean	LiDAR, RGB-D	Graph Frontier	?	Mesh	\$44
	C43 Kim	SIM	Indoors	2D Laser, RGB-D	Frontier	+	?	\$47
	C7 Ronck	Wheeled, Aerial, Legged	Subterranean	LiDAR, RGB-D	Frontier	+	Mesh	\$44
	C83 Takib	Aerial	Subterranean	RGB-D	Grid	?	low Band. ch.	\$
	C9 Ebadi	Wheeled	Subterranean	LiDAR, RGB-D	?	?	Mesh	\$44
	C10 Rei	SIM	Indoors	/	Orientation, Grid	/	/	/
	C11 Shrestha	SIM	Indoors	/	Learning, Frontier	/	/	/
	C12 Eldermix	Wheeled	Indoors	RGB-D	Voronoi	?	?	\$
	C16 Bucher	Aerial	Indoors	RGB-D	Random trees, Next Best	Mid-Conf.	?	\$
	C17 Müller	Wheeled	General (but limited)*	Sonar, RGB	/	/	/	\$ (phone)
	C18 Tarditi	Wheeled	Tunnels	LiDAR	/	/	Mesh	\$44
	C19 Dang	Aerial	Subterranean	LiDAR, RGB	Graph	/	Mesh	\$44
	C20 Stumm	Wheeled	Indoors	3D Laser, Sonar, RGB	Next Best View, Frontier*	/	/	\$44 (unreal)
	C23 Zhou	Wheeled	Indoors	/	/	/	/	\$ (phone)
	C24 Faisal	Wheeled	General	/	/	/	IoT	\$ (unreal)
	C25 Coral	SIM	Indoors	/	Grid	/	/	/
	C37 Repadurkar	Wheeled Aerial	Indoors	RGB-D	Random trees	/	/	\$
	C45 Dai	Aerial	Indoors	RGB-D	Frontier	/	/	\$
	C46 Schmidt	Aerial, SIM	Indoors	/	Sampling	/	/	/
	C47 Palani	Aerial	General	LiDAR	Frontier	/	/	\$4

† - blue lock

† - samples pose by new points instead of just frontiers
 * - Due to robot's small size / low obs. to clear obstacles
 (\$) = \$-1/2