

Sheet1

A: Camino  
B: Fallos Positivos  
C: Pierde la Muestra / Seek Action / La camara  
D: Otro rover

Tree 1					
pfile	plan	time	original plan	repaired plan	
				reused actions	repaired actions
1	1	1.03	2	1	1
1	1	0.71	1	0	2
2	1	0.14	4	4	5
2	1	5.63	3	3	4
2	1	0.15	2	1	1
2	0	0.84	1	0	0
3	1	0.26	4	2	3
3	1	0.10	3	3	4
3	1	0.10	2	2	3
3	1	1.27	1	0	3
4	1	0.14	2	2	3
4	1	0.11	1	1	2
5	1	5.83	2	0	4
5	1	0.18	1	1	2
6	1	0.94	3	3	4
6	1	0.17	2	0	0
6	0	27.40	1	0	3
7	1	0.97	3	1	5
7	1	0.12	2	2	3
7	1	2.19	1	0	3
8	1	0.36	2	2	3
8	1	0.35	1	1	2
9	1	21.92	2	0	4
9	1	0.21	1	1	2
10	1	0.65	2	2	3
10	1	2.15	1	0	2

**Fallo**

B calibrated-camera0-rover0,ye  
A <can\_traverse-rover0-w3-w2  
A <at-rover0,waypoint2>  
C <at\_soil\_sample-waypoint1,r  
A <visible\_from-objective1-way  
Not found plan <can\_traverse-rover0-waypo  
A <at-rover0,waypoint1>  
A <at-rover0,waypoint2>  
A <at-rover0,waypoint2>  
C have\_soil\_analysis-rover0-w  
A <at-rover0,waypoint2>  
C <calibrated-camera1-rover0,l  
A <visible\_from-objective1-way  
A <at-rover0,waypoint2>  
A <at-rover1,waypoint1>  
Not found plan <visible\_from-objective1-wa  
D  
A <visible\_from-objective1-way  
C <calibrated-camera1-rover0,l  
A <visible-waypoint1-waypoint3  
A <at-rover0,waypoint2>  
A <at-rover0,waypoint3>  
A <visible\_from-objective1-way  
C <calibrated-camera1-rover0,l  
A <at-rover0,waypoint6>  
A <can\_traverse-rover0-waypo

se descalibra

### Solución

```
es  
,false>]
```

```
not>  
/point1,false>  
int1-waypoint2,false>
```

aypoint1,yes

```
not>  
/point3,false>
```

y point2,false>

### Otro rover

```
/point1,false>  
not>  
3,false>
```

```
/point4,false>  
,not>
```

int4-waypoint1,false>

### Fallo

### Solución

```

<visible_from-objective1-waypoint3,false>  Navigate a otro waypoint, y calibra la cama
<can_traverse-rover0-w3-w2,false>]
<at-rover0,waypoint2>
<at-rover0,waypoint2>
<visible_from-objective1-waypoint1,false>
<can_traverse-rover0-waypoint1-waypoint2,false>
<at-rover0,waypoint1>
<at-rover0,waypoint2>
<at-rover0,waypoint2>
have_soil_analysis-rover0-waypoint1,yes
<at-rover0,waypoint2>
<calibrated-camera1-rover0,not>
<visible_from-objective1-waypoint3,false>
<at-rover0,waypoint2>
<visible_from-objective1-waypoint1,false>
<at-rover0,waypoint4>

<visible_from-objective1-waypoint1,false>
<at-rover0,waypoint3>
<visible-waypoint1-waypoint3,false>
<at-rover0,waypoint2>
<at-rover0,waypoint3>
<visible_from-objective1-waypoint4,false>
<visible_from-objective1-waypoint4,false>
<at-rover0,waypoint6>
<can_traverse-rover0-waypoint4-waypoint1,false>

```

ra nuevamente