



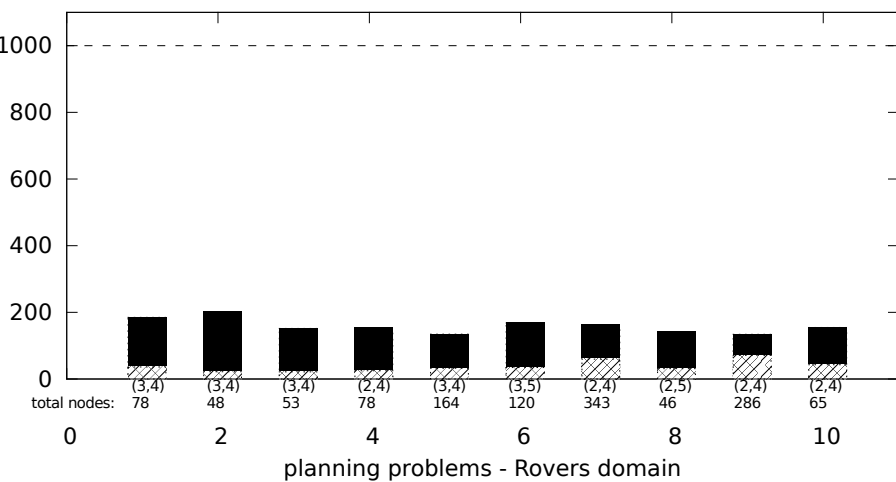
Results and evaluations


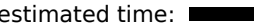
Cesar Augusto Guzman Alvarez

March 25, 2014

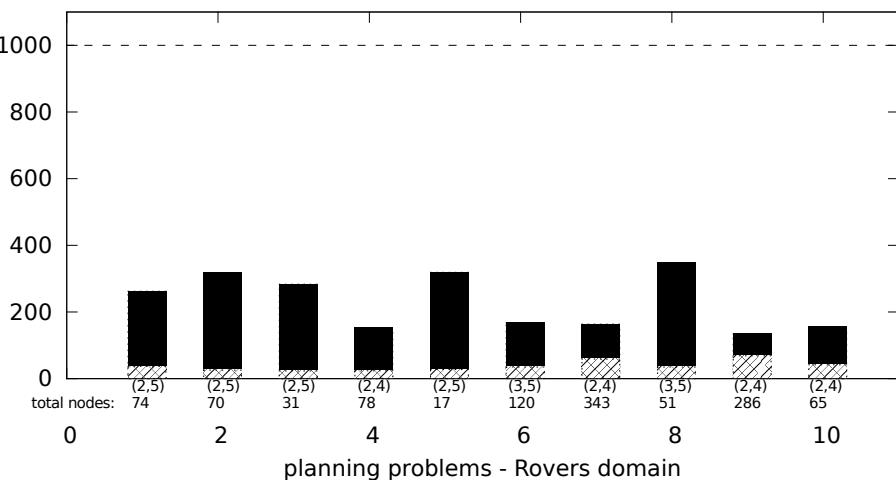
real time:  estimated time:  time limit: - - - -
 planning horizon l and depth d : (l, d)



real time to generate the search tree 1



real time:  estimated time:  time limit: - - - -
 planning horizon l and depth d : (l, d)

real time to generate the search tree 1



real time:  estimated time:  time limit: - - - -
 planning horizon l and depth d : (l, d)

real time to generate the search tree 1

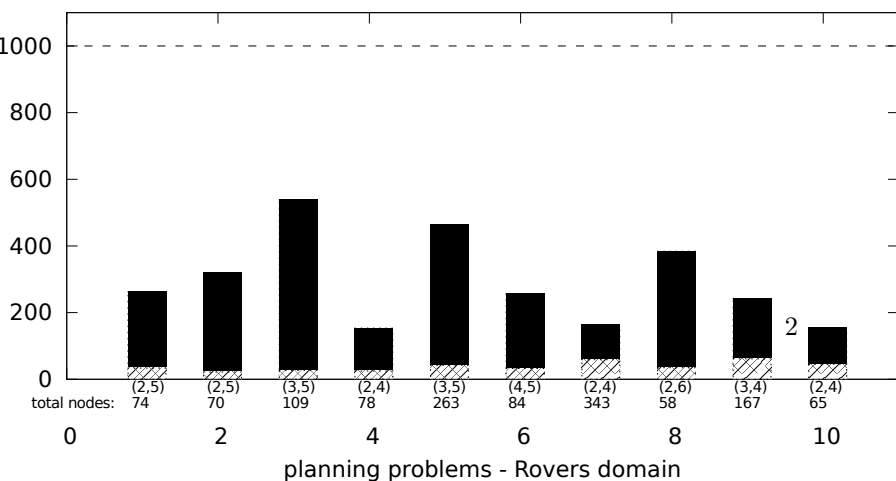

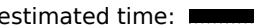
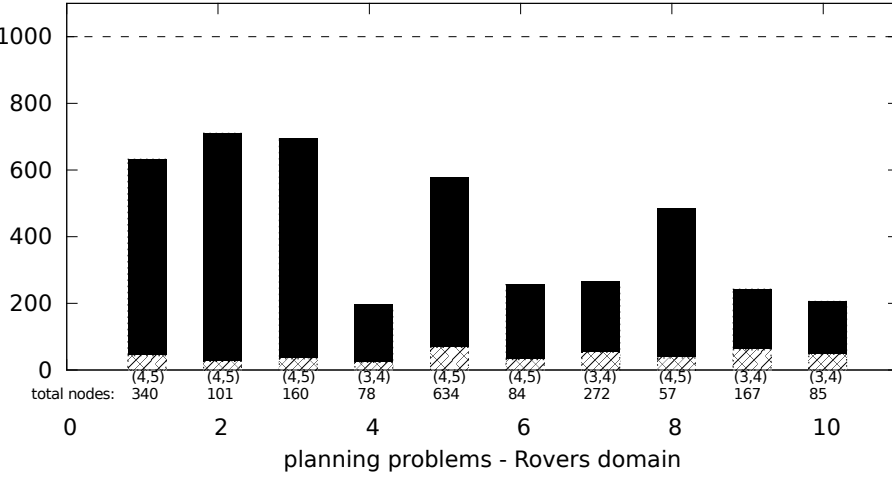

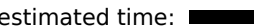


Figure 1: ArgMax - 1. \mathcal{T}_1 . Fig 1: 15, Fig 2: 30, Fig 3: 45.

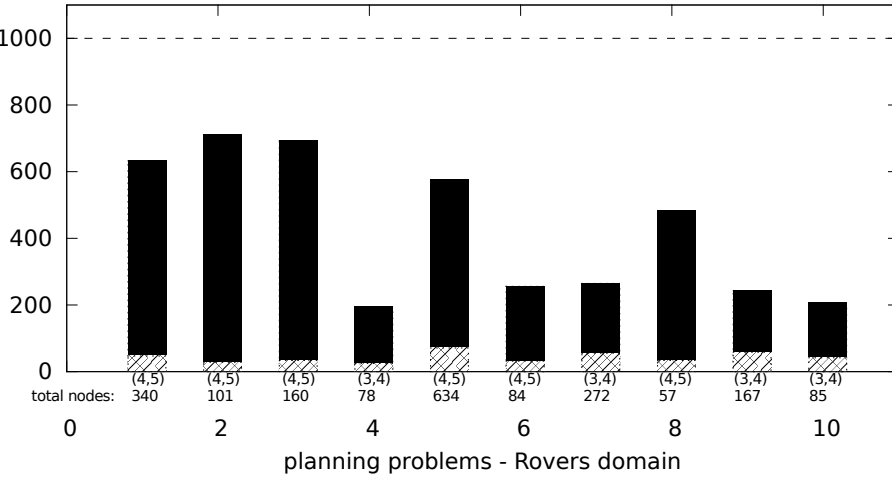
real time:  estimated time:  time limit: - - - -
 planning horizon l and depth d: (l, d)


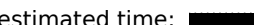
real time to generate the search tree 1



real time:  estimated time:  time limit: - - - -
 planning horizon l and depth d: (l, d)

real time to generate the search tree 1



real time:  estimated time:  time limit: - - - -
 planning horizon l and depth d: (l, d)

real time to generate the search tree 1

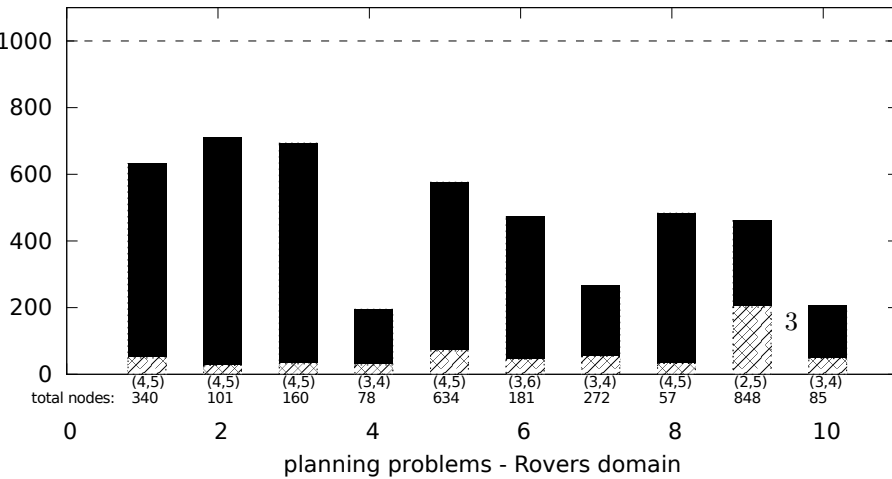


Figure 2: $\text{ArgMax}.\mathcal{T}_1$. Fig 1: 15, Fig 2: 30, Fig 3: 45.