## V1 (no originality)

Receding Horizon NBV with RRT

## V2 (no originality)

Receding Horizon NBV with RRT\* (reconnect during tree growing)

## V3 (no originality)

Is a bug

## V4 (little originality)

Receding Horizon NBV with an information gain tunned for higher vision coverage along with range coverage

## **V4\_5: (originality)**

Use RRT to search for NBV (high range information gain),

After range exploration is considered accomplished, use GA to solve TSP to go through all the potential spots for vision coverage

## **V5: (originality)**

Use RRT to search for NBV (high range information gain),

Guide the robot to NBV using Dijkstra (or A\*) with a costmap that has a lower cost where walls can be scanned

After range exploration is considered accomplished, use GA to solve TSP to go through all the potential spots for vision coverage

## **V6: (originality)**

(under development)

Solve TSP in every iteration

## V7: (originality)

(under development)