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# A New Exploration Method Based on Multi-layer Evidence Grid Map (MLEGM) and Improved A\* Algorithm for Mobile Robots

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Author(s)

Esmaeili, E. ; Dept. of Electr., Comput. & IT Eng., Qazvin Azad Univ., Qazvin, Iran ; Azizi, V. ; Samizadeh, S. ; Ziyadloo, S.  
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## Author(s)

Esmaeili, E.  
 Dept. of Electr., Comput. & IT Eng., Qazvin Azad Univ., Qazvin, Iran  
 Azizi, V. ; Samizadeh, S. ; Ziyadloo, S. ; Meybodi, M.R.

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