**LISTED RESPONSE TO COMMENT/SUGGESTIONS OF**

***REVIEWER 1***

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| ***No*** | ***Reviewer’s Comment/Suggestion*** | ***Author’s Comment*** | ***Action Taken\*\*\**** |
| 1 | Please explain the difference between reference [9] and this paper. They are both presented the MOD\* Lite methods. | Thank you for your comments and suggestions. Our conference paper [9] is the prior version of this study. However, we extended the MOD\* Lite method in this paper and added a soft computing genetic algorithm (MOGPP and SPEA2) for comparison. Experimental study is redesigned and carried out from scratch. | No change was done on the manuscript. |
| 2 | Please check the type errors in the paper, such as "For the experimental study, MOD\* Lite is is realized," in Page 5 (Line 4-5). I find several errors. In Section IV, the word "multi objective" does not have the '-'. But, in the previous sections, the word is "multi-objective." Please correct them. | All occurrences of the word “multi objective” are replaced with “multi-objective” to keep consistency. We went through the manuscript and corrected all errors and typo as requested. | Corrections are done in accordance with the reviewer’s comments. |
| 3 | In this paper, the MOD\* Lite method is applied to 2D UAV problem whose environment is represented by the square cells. Please explain how to transform the cell-base environment to the real space in real application. | D\* is a domain-independent search algorithm so is MOD\* Lite. A potential user needs to specify the set of states, the set of action, the state transition function, an initial state and the set of goal state. In order to exemplify MOD\* Lite we selected an application domain where the environment is a 2D grid based navigation map and there are two independent objectives. MOD\* Lite, similar to D\*Lite naturally does not restrict to any environment or domain (firmly environment independent). This issue was mentioned in Section III, Subsection B. Overview. We extended this explanation.  For the 2D UAV application, the grid-based environment can be transformed into any discrete representations by redefining state and action schemas. For example, one can add diagonal moves to the set of actions or change grids to hexagons. | We appended a sentence to the last paragraph of In *Section III, B. Overview* to clarify the issue. |
| 4 | In Algorithm1, I suggest to put the PLAN() procedure to the top and indicate that it is the main procedure to avoid confusion. | PLAN() procedure in Algorithm 1 is placed at the top of other procedures. Also it is stated that PLAN() procedure is the main one in Section III-D. | Algorithm 1 is reorganized and the paragraph just before the Algorithm 1 is revised to indicate that PLAN() is the main procedure. |
| 5 | In Section III, it seems not easy to be understand about the algorithms presented in this section. Can you illustrate the important concept of the algorithm by using another figure? | MOD\* Lite is the extension of D\* Lite algorithm and it makes use of the base functions in D\* Lite. That’s why we followed the same way of algorithmic presentation as done in D\* and D\* Lite papers/documents to be consistent. Since the algorithms are tightly coupled, really we couldn’t find a way of visualizing the method in a figure. | No change was done on the manuscript. |
| 6 | In Fig. 6, why MOA\* requires the most computing time? | In Figure 6, actually MOA\* does not have the most computing time but rather MOGPP takes the utmost time to find a path in all sensor ranges. | No change was done on the manuscript. |
| 7 | For MOGPP method, please explain that how to judge the chromosome is non-dominated and how to update or replace the old chromosome. | The judgement of chromosome domination was described in Section IV (3rd paragraph from the bottom of the section). In MOGPP, each chromosome encodes a valid path from initial location to target. Each generated path represents an individual in population. These individuals are kept in a directed acyclic graph to cope with multi objectivity. The vertices and edges represent individuals and domination of multi objective path costs of these individuals, respectively. If a path cost of an individual dominates to that of another, an edge is established between these individuals' vertices. Non-domination and equality do not come up with an edge. When an individual is generated and desired to be added to population, the cost function of this individual is compared with existing individuals' costs and required edge connections are established. The directed acyclic graph structure has the same essence and representation with MOD\* Lite' s priority structure.  At each evolution phase, predefined number of best individuals are chosen from topologically sorted directed acylic graph and transferred to new population. After selecting two mates by roulette-wheel selection method, crossover and mutation operations are applied to update old chromosomes.  As a single chromosome stands for a valid path in MOGPP, newly generated children should also obey this rule. Thus, genetic operations must guarantee that newly generated children are consistent and have valid paths. For crossover operation after choosing parents; one of the random intersecting cells of those parents are selected. Both parents' paths are split from that cell, swapped with each other and merged to other parent's path starting from that cell. On the other hand, mutation is done as follows; a cell from corresponding individual' s path is selected randomly first. This cell is the reference point to split up the path into two sub-paths. Then, the sub-path which contains target location is thrown away and a random path to the target is generated instead.\* | We enlarge MOGPP iteration details on Section IV. (1st paragraph from the bottom of the section) |
| 8 | In Section V-B, page 10, the agent has found three paths with costs (15, 200), (18, 230) and (23, 260). The agent tends to choose the path with cost (18, 230). Please explain why it does not choose the path with (15, 200) since (15,200) dominates (18,230). | Thanks for your correction. The path costs are updated as (15, 260), (18, 230) and (23, 200) where none of the path costs could dominate each other. In such cases the middle one, (18, 230), is selected by the agent. | Corrections are done in Section V-B as requested. |
| 9 | In Section V, both MOD\* Lite and MOA\* method require re-plan while the environment changes. Please state that why MOA\* requires much time compared with MOD\* Lite. | MOA\* is an off-line path-planning algorithm and needs to re-plan from scratch when environment or agent state has changed. On the other hand, MOD\* Lite is an on-line incremental path planning algorithm just like D\* Lite and capable of considering only unexplored parts of environment during re-planning phase. That's why MOA\* takes much more time on finding a path compared to MOD\* Lite. | In the last paragraph of Section V-B, we added the information that MOD\* Lite is incremental but MOA\* is offline algorithm. |

*\* Visualized crossover and mutation operations for MOGPP can be found on appendix.*

**Appendix**

**Crossover and Mutation Visualization for MOGPP**

