

HM-EQA Task: I'm looking for the banjo that I usually keep around.
A) Resting in the living area
B) On the bedroom wall
C) Hanging in the hallway
D) Leaning against the kitchen cabinets

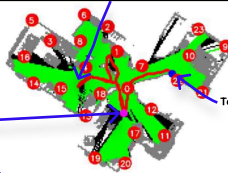
At timestep 105: VisuallyAnalyzeIfBanjoInLivingArea() with a type algorithm and a rationale: We have been exploring the living area to find the banjo; now we should visually analyze if it's present in the living area. The joint analysis of images from the living area revealed no visible presence of a banjo, confirming that it is not located there. Therefore, further exploration in other potential areas, such as the bedroom or kitchen, is necessary to locate the banjo.



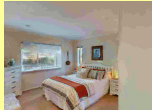
At timestep 105: 2.1. Explore(find bedroom) # Search for the bedroom with a type explore and a rationale: The banjo was not found in the living area, so we should explore the next possible location, which is the bedroom.



At timestep 1: 1.1. Explore(find living area) # Search for the living area with a type explore and a rationale: The task begins with exploring the living area for the banjo, and no exploration has occurred yet.



At timestep 265: The robot has confirmed the presence of the banjo in a bedroom at point 10, resting against the wall, which aligns with one of the task's options. This confirms the mission objective and constitutes progress towards the task. The task required the exploration of all potential locations for the banjo, which included the living area, bedroom, hallway, and kitchen. The progress log indicates that the living area was thoroughly explored and the banjo was not found there. The exploration then moved to the bedroom, where the banjo was confirmed to be hanging on the wall. This matches one of the given options ('On the bedroom wall').
Answer B



Trajectory → Time → Spatial Relationship →

Occupancy Grid with Landmarks

