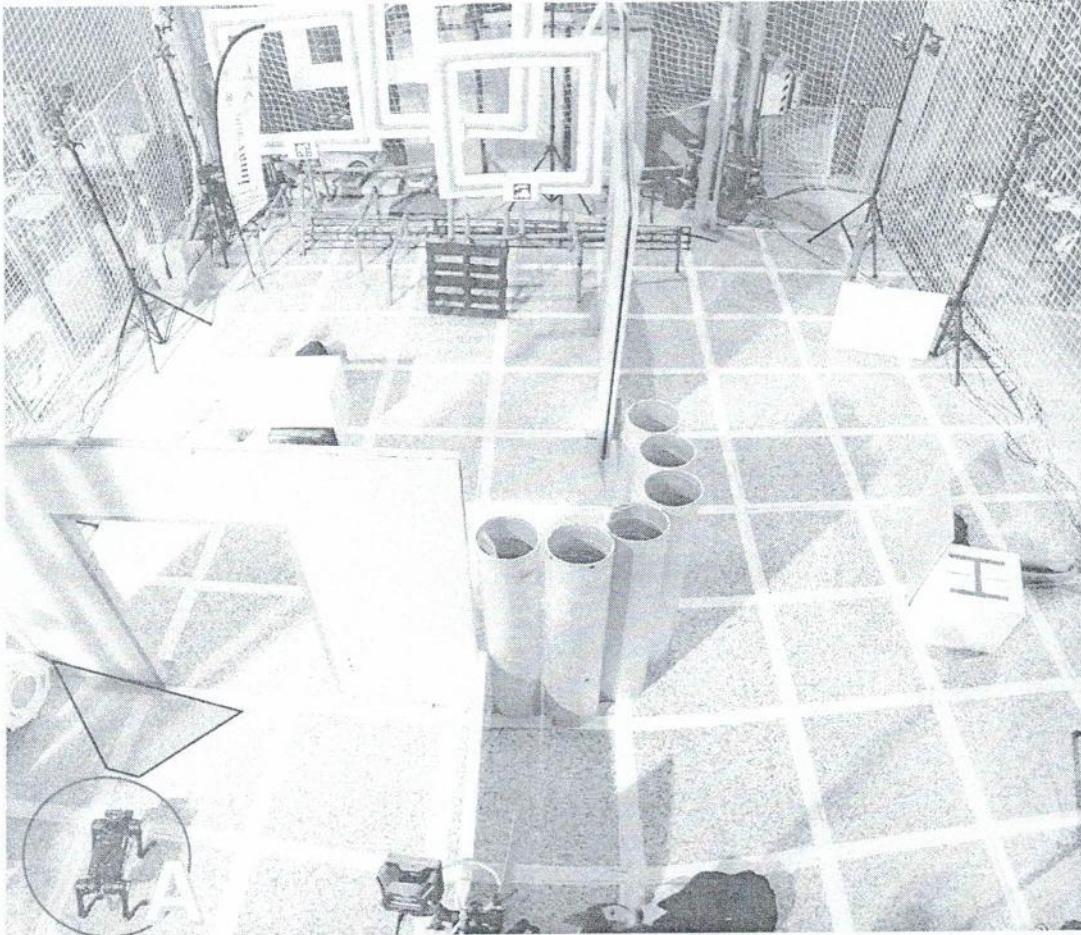
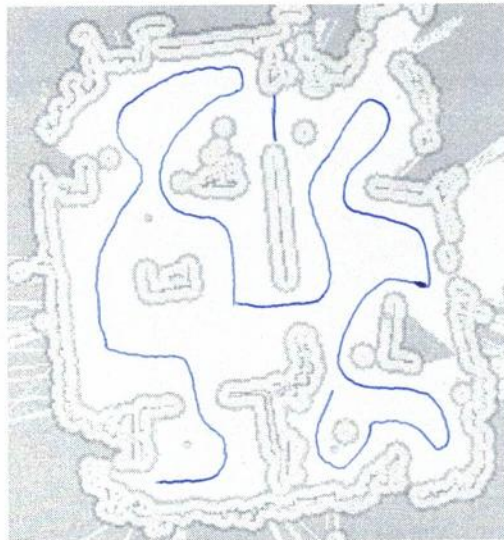


Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.

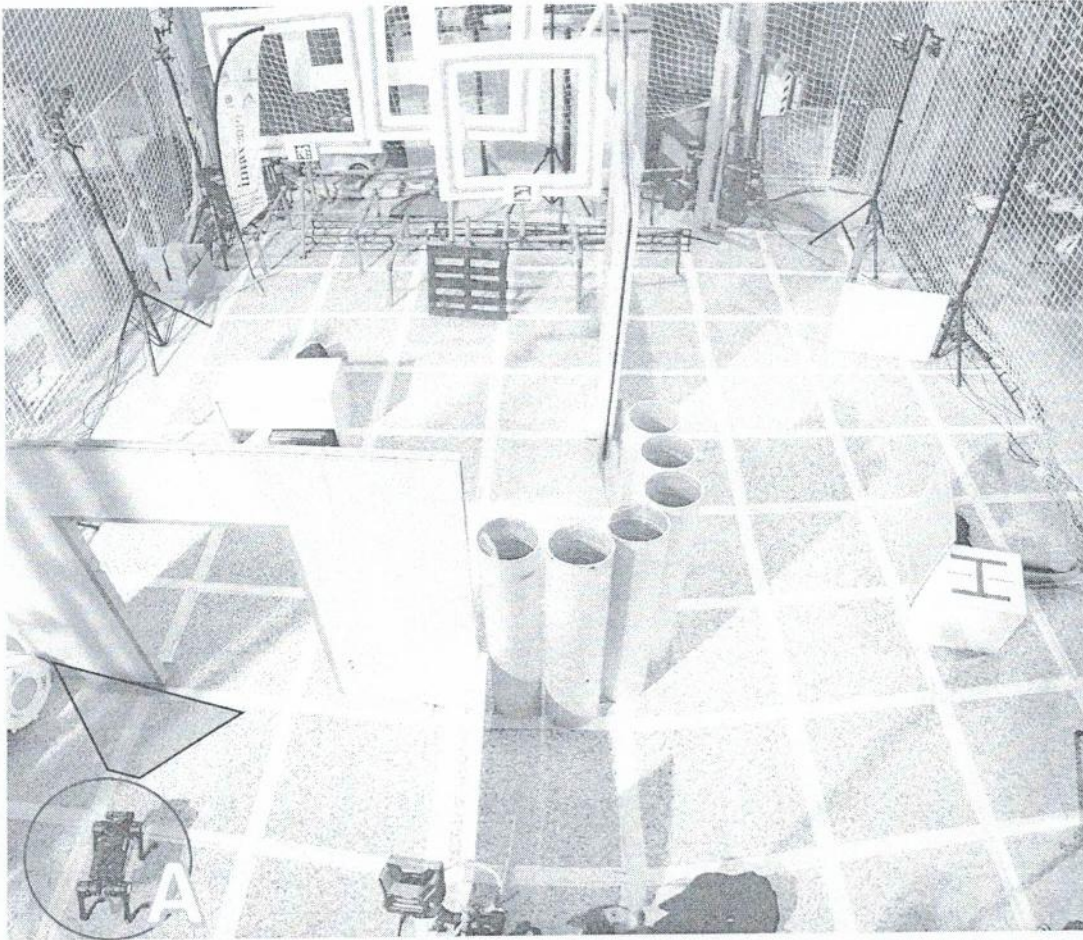


A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.

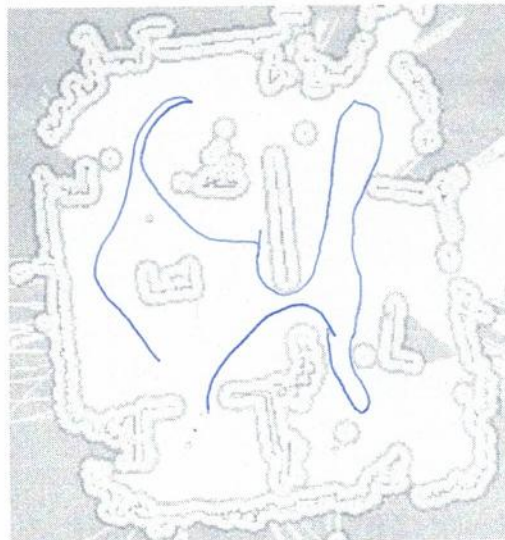


Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



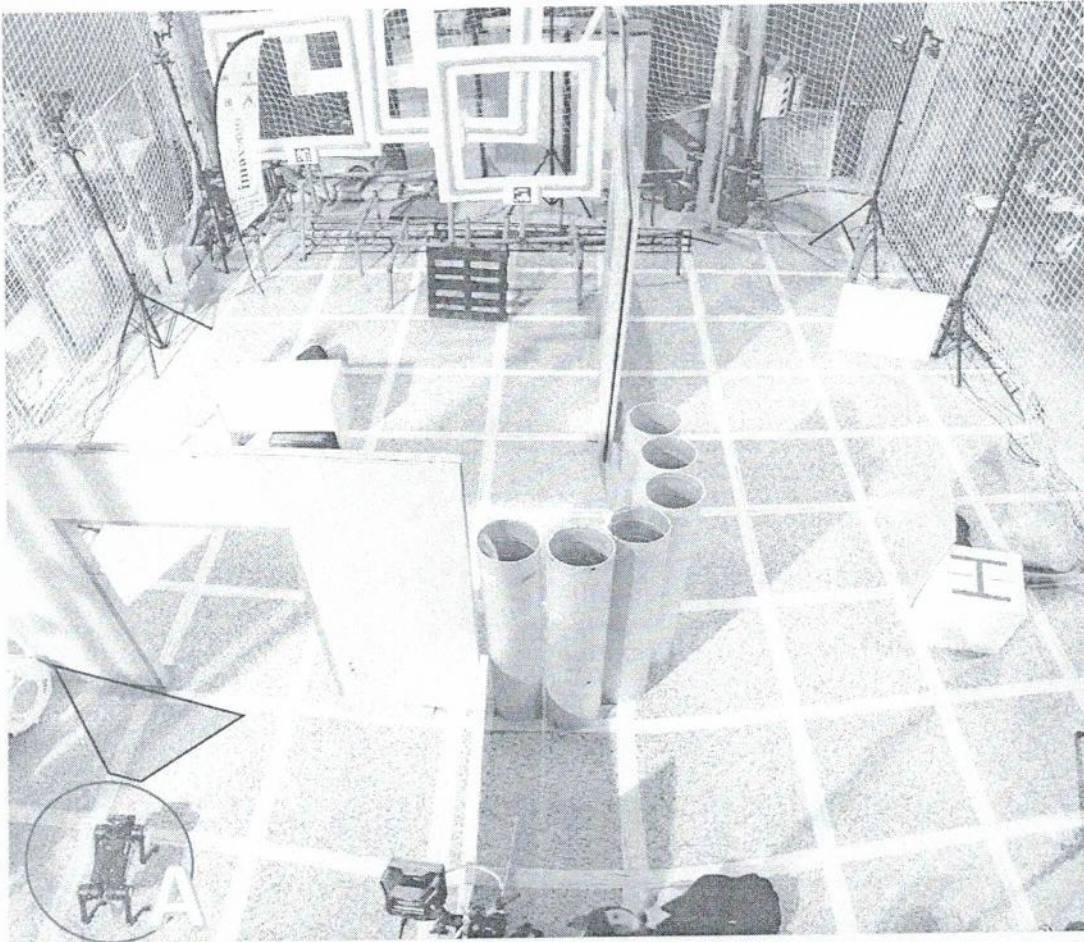
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



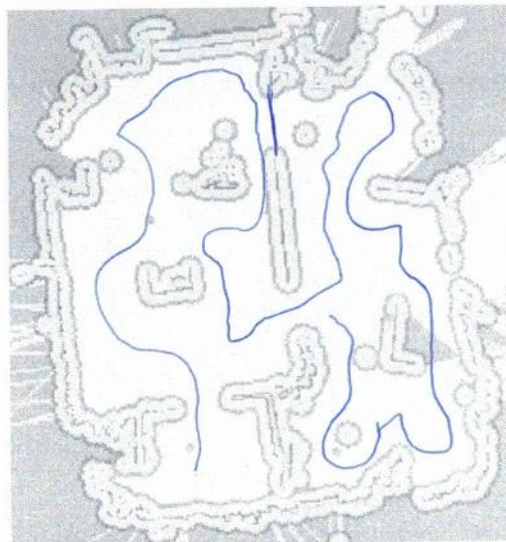
Vassil
Garcia

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



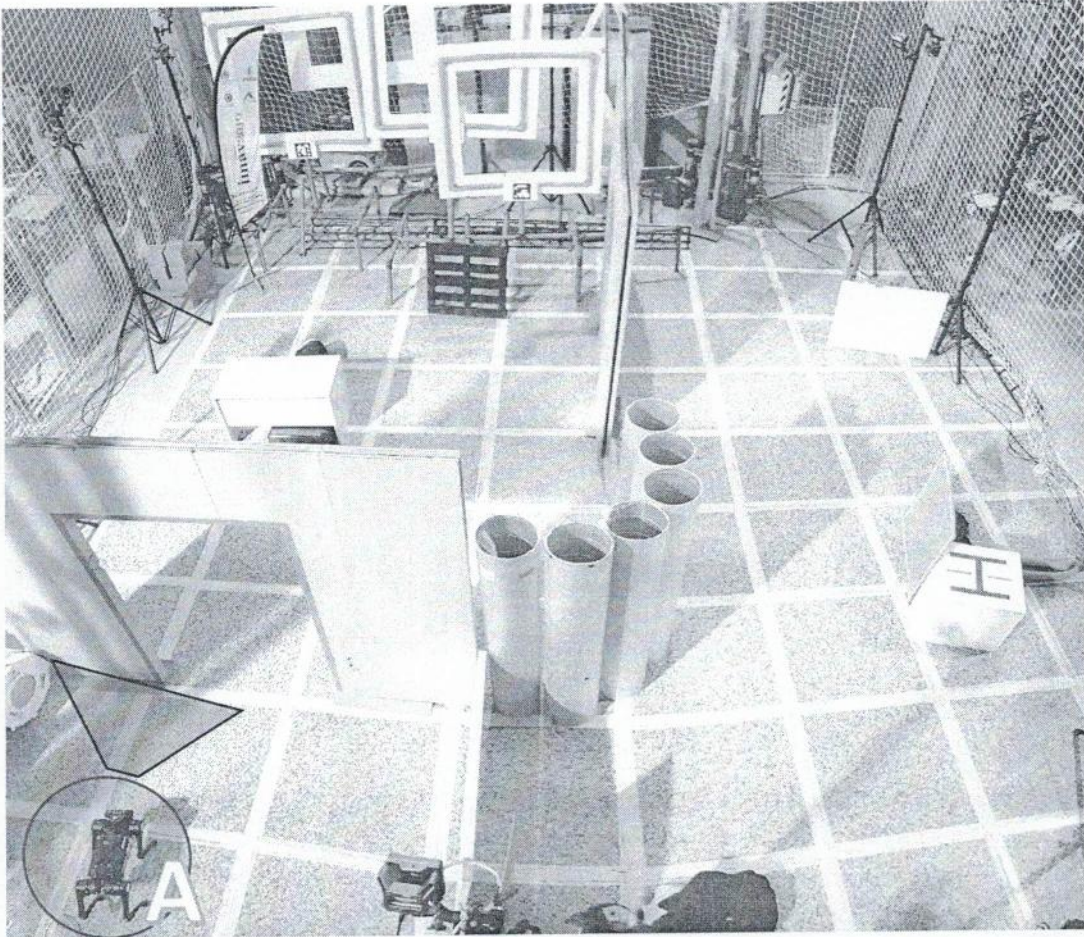
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



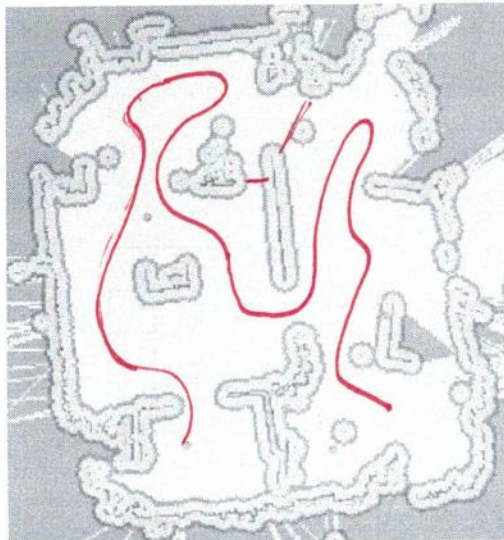
Margate Sanatin

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



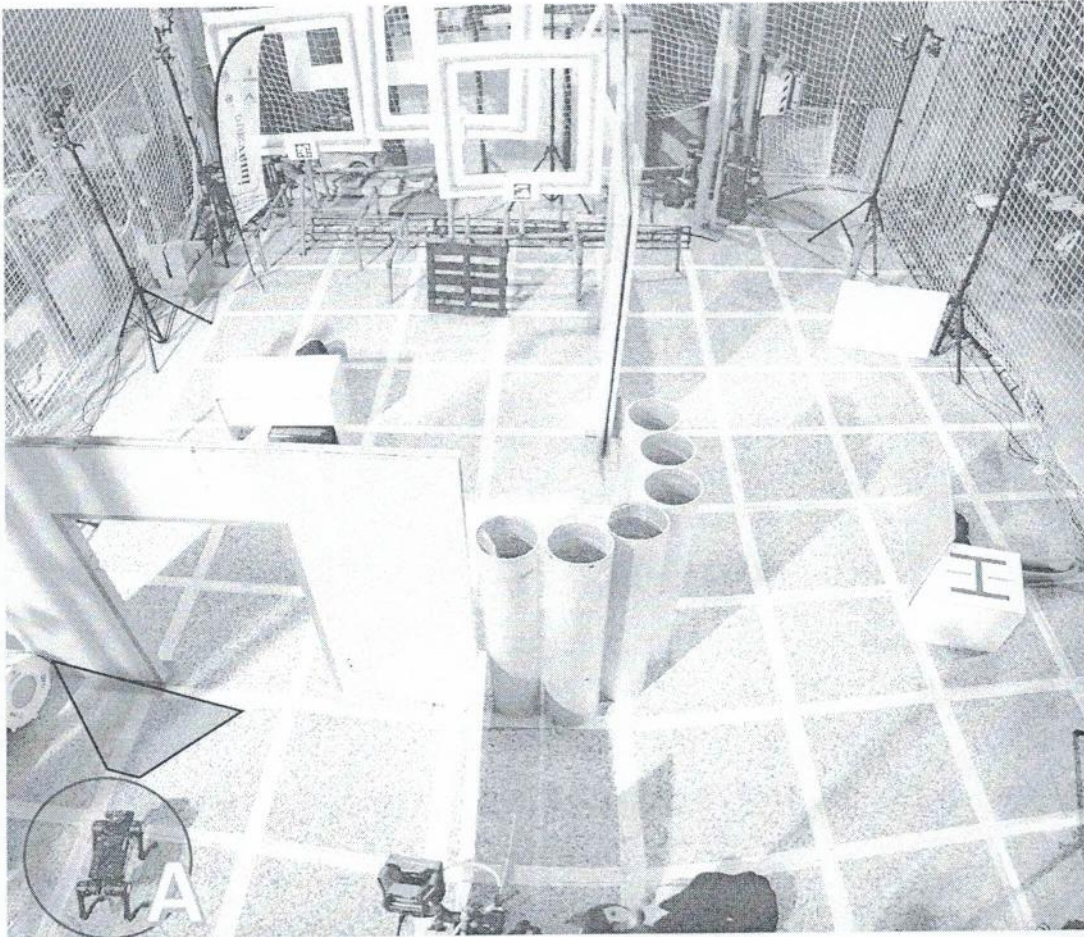
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



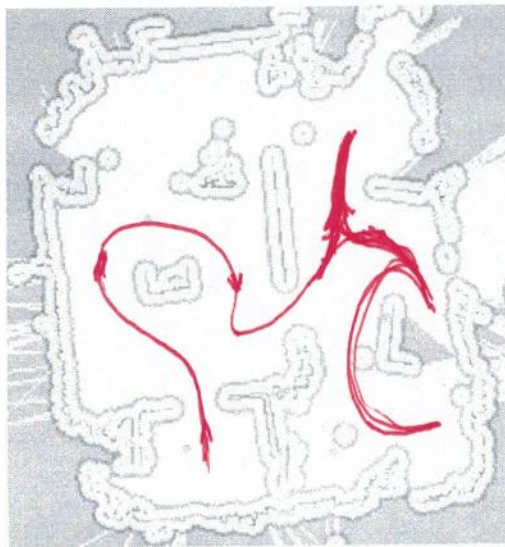
Juan Mateos

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



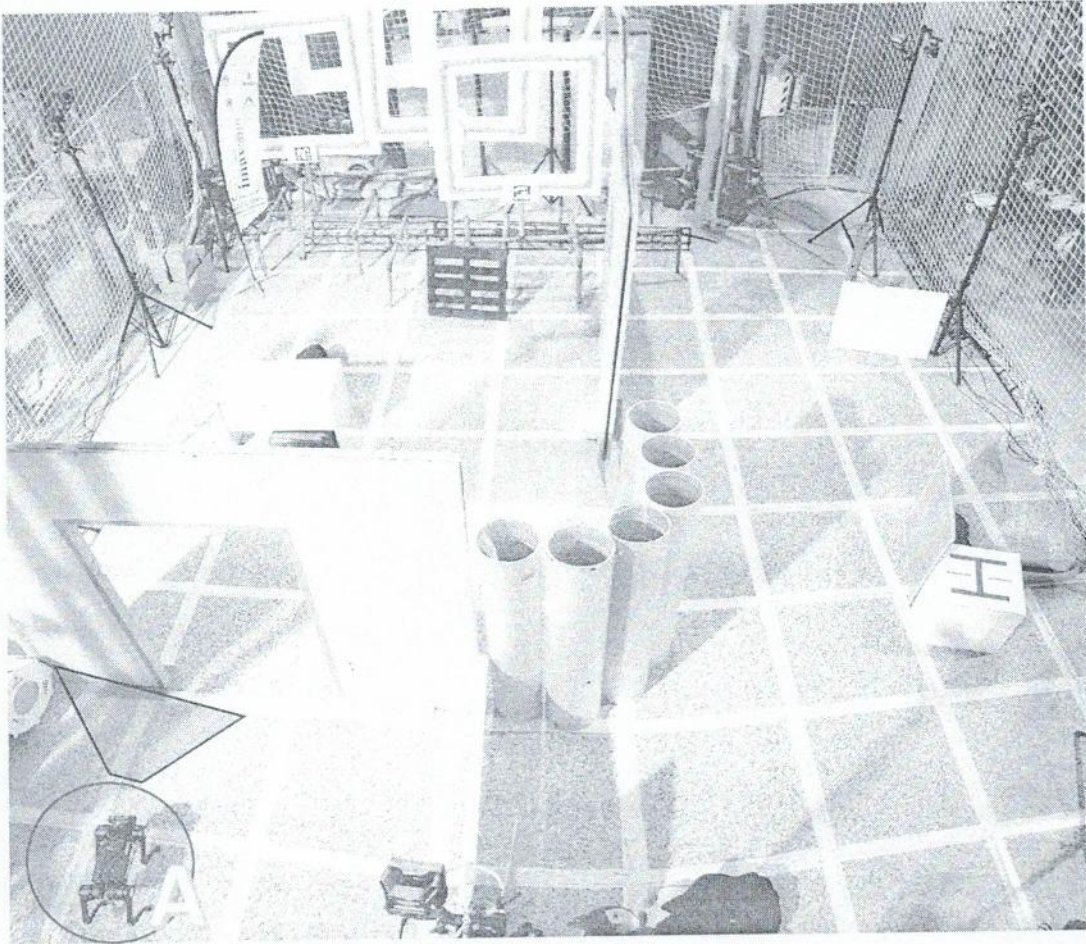
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



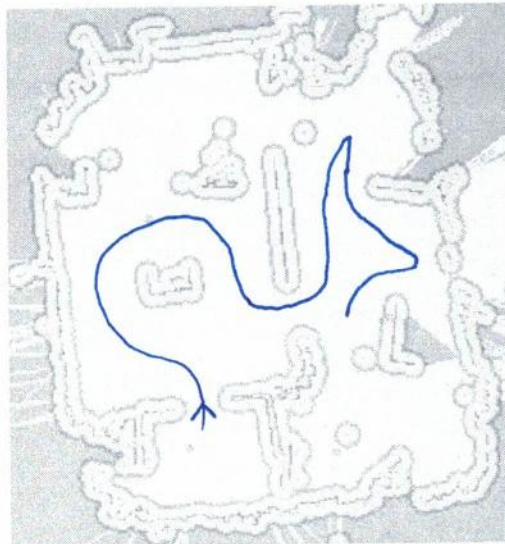
Manuel Barrera / mel4

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.

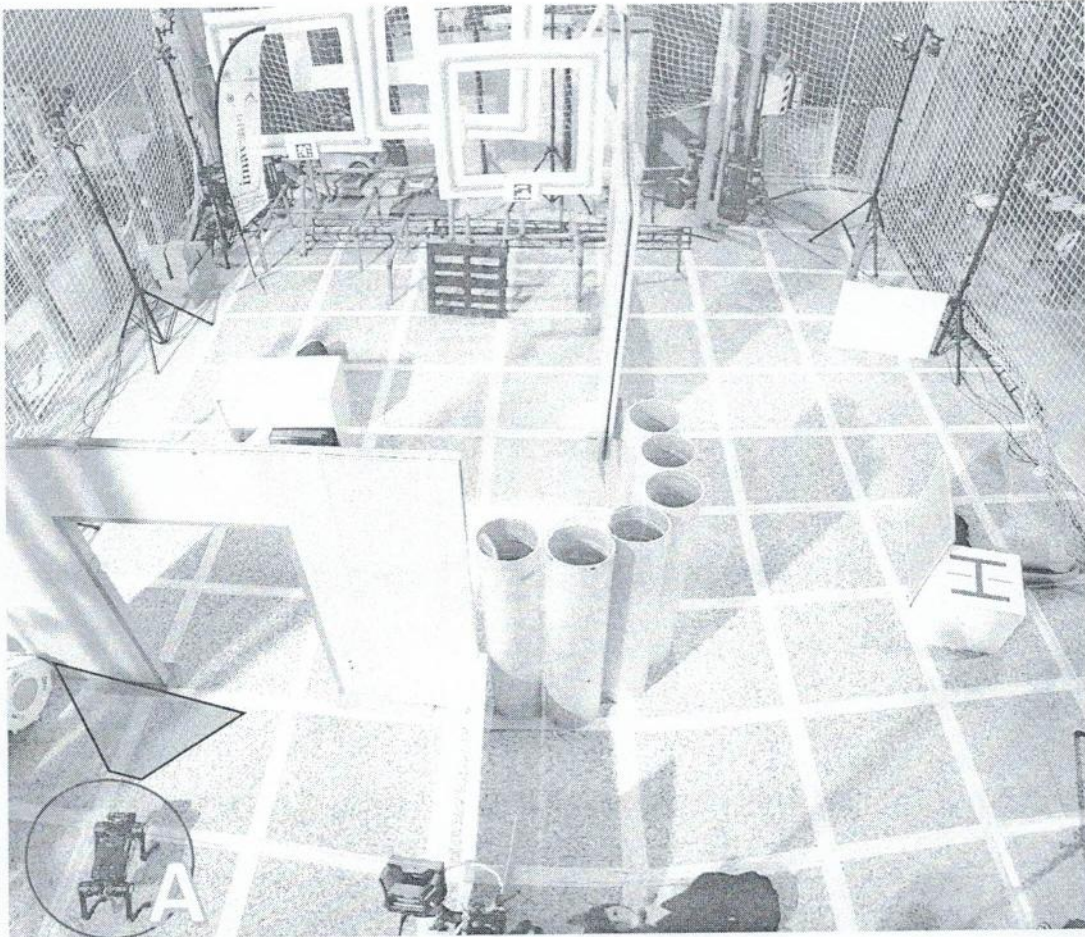


Javier JF

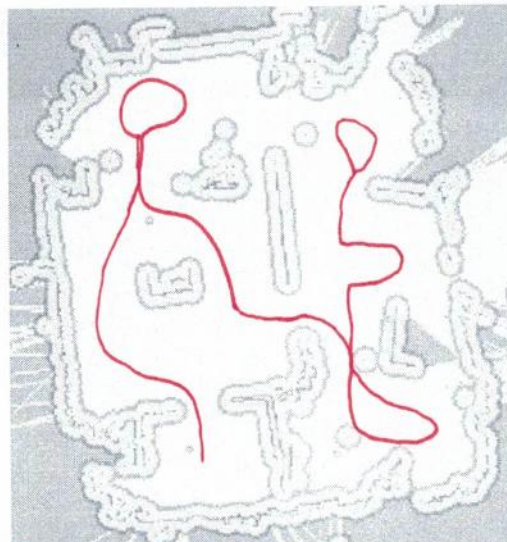
Javier Jiménez
Fernández

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



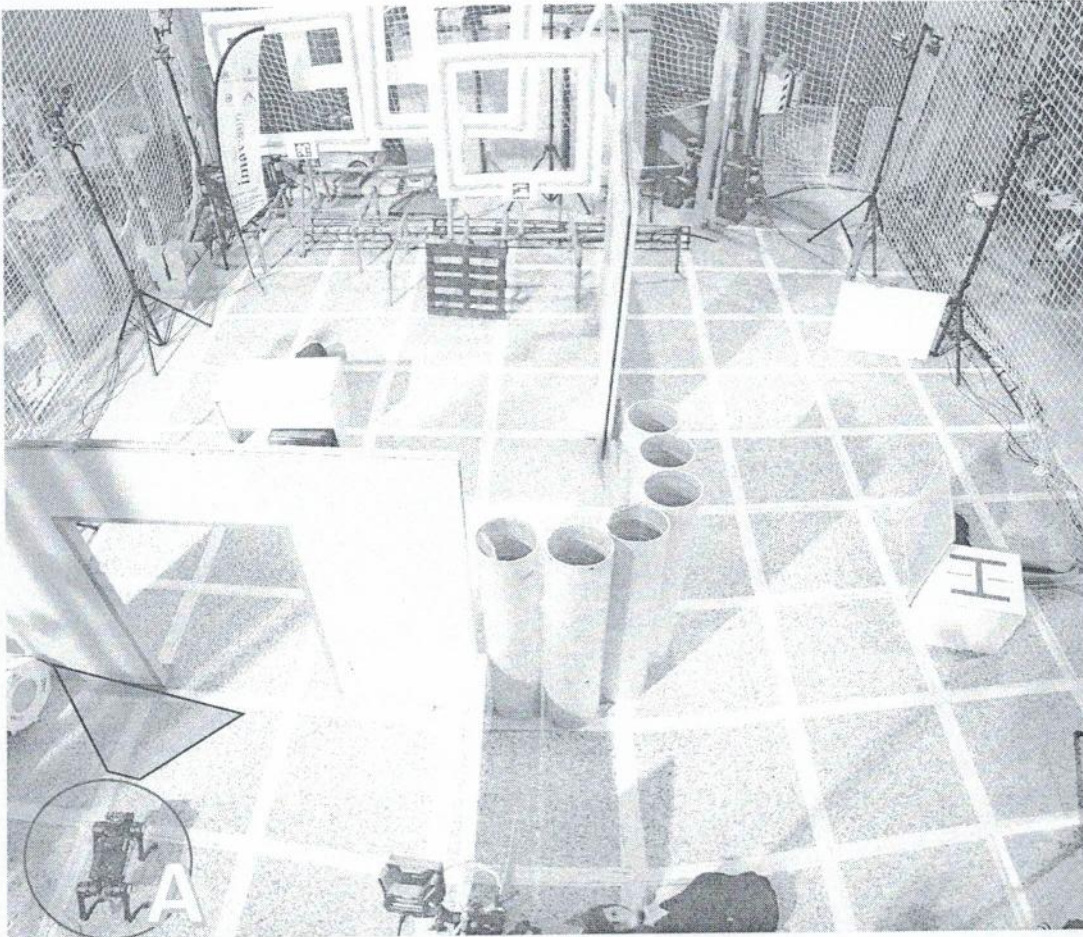
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



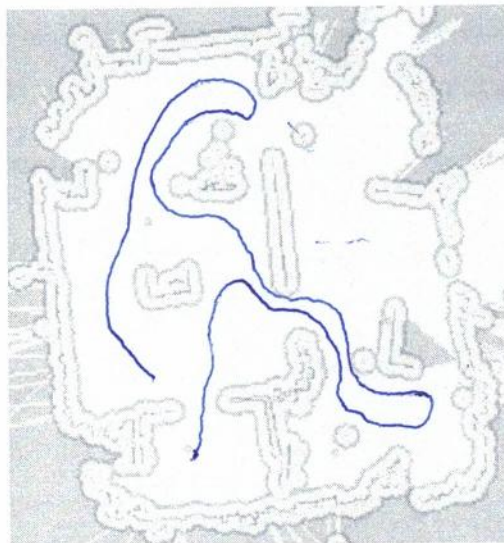
Rafael Pérez
[Signature]

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



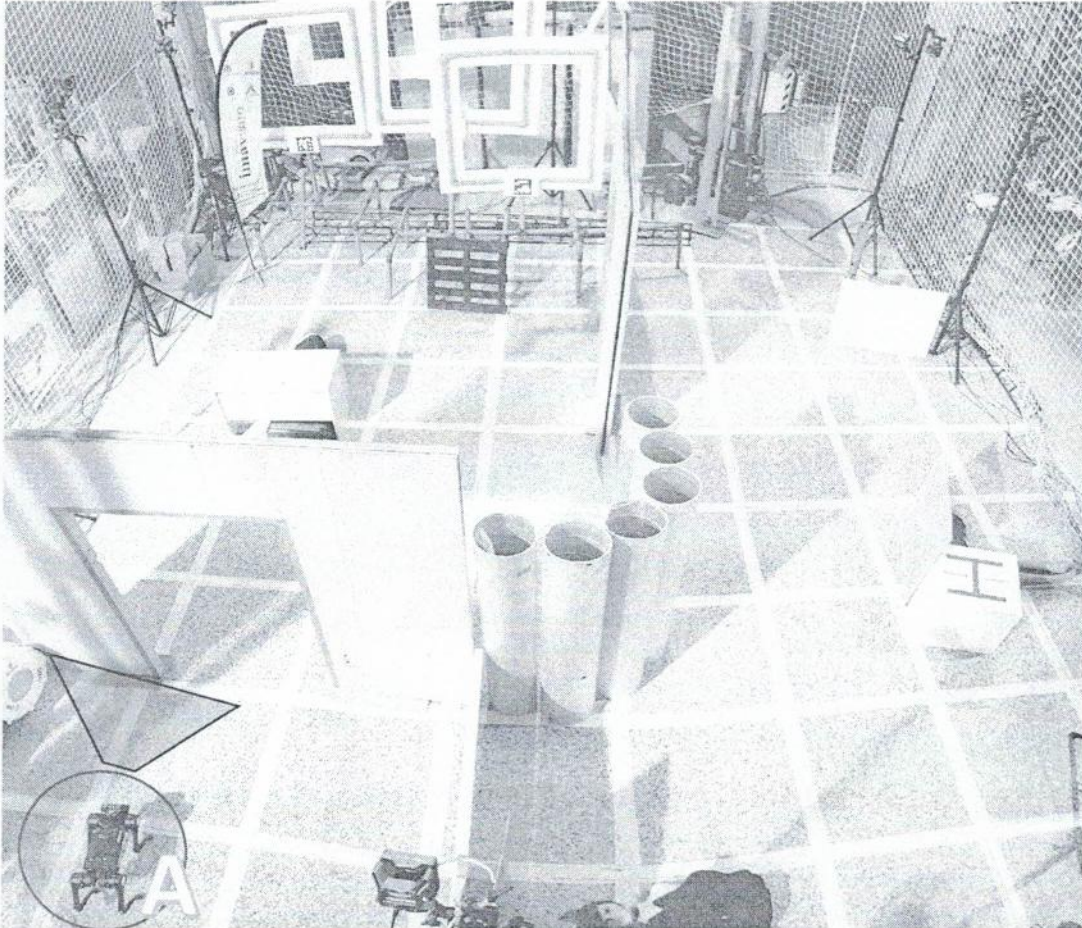
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



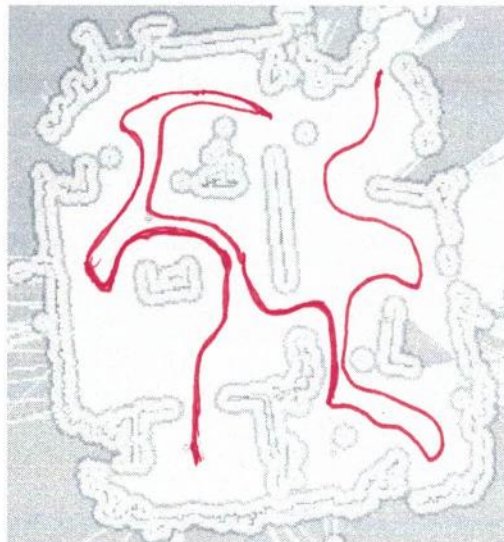
Xavier Melero Deza

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.

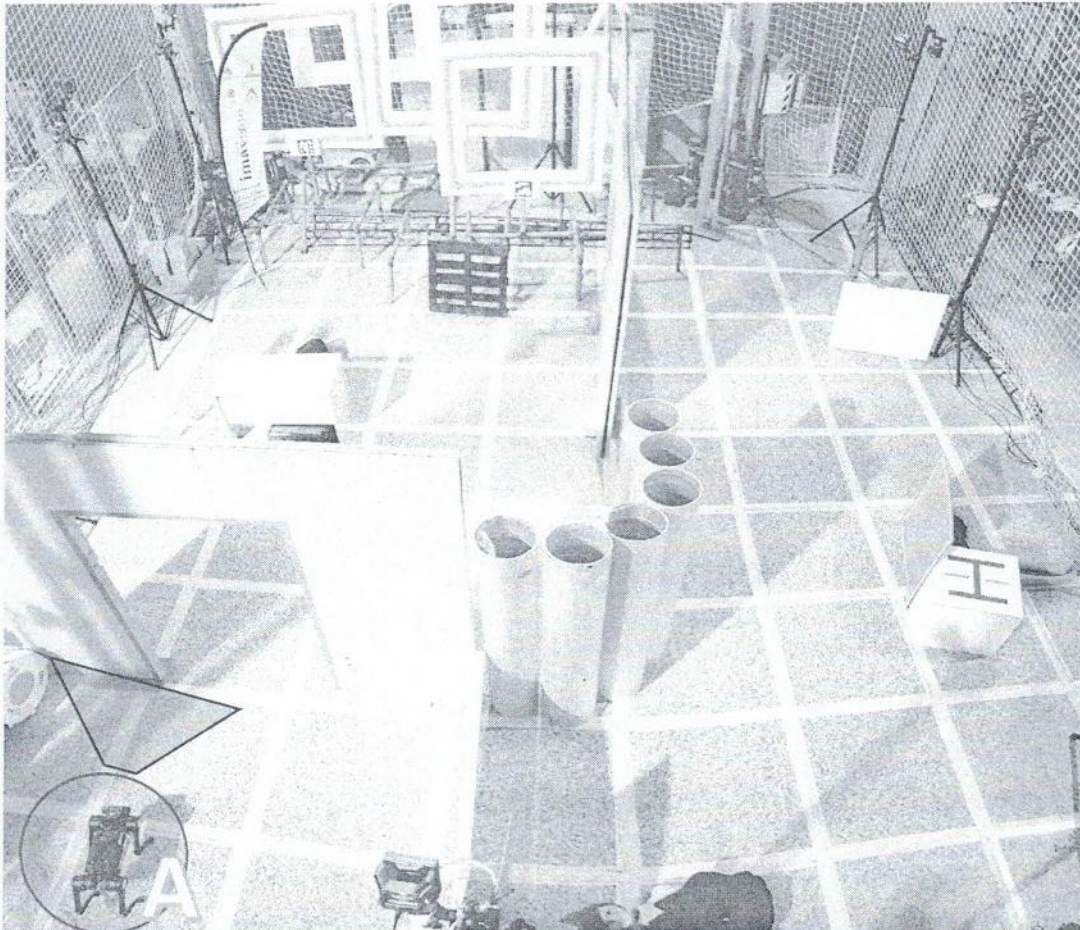


A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.

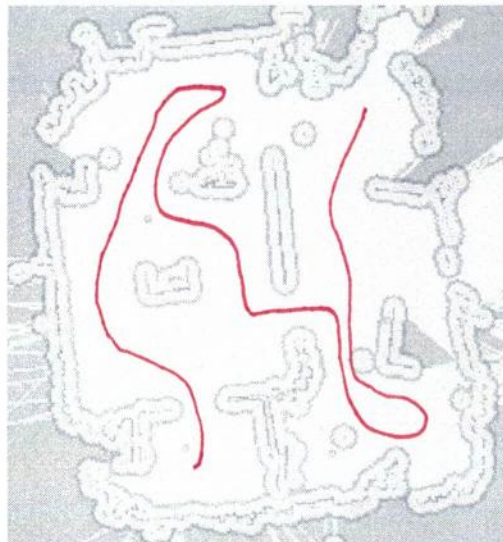


Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer). starting from point "A" where the robot is located.



A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.

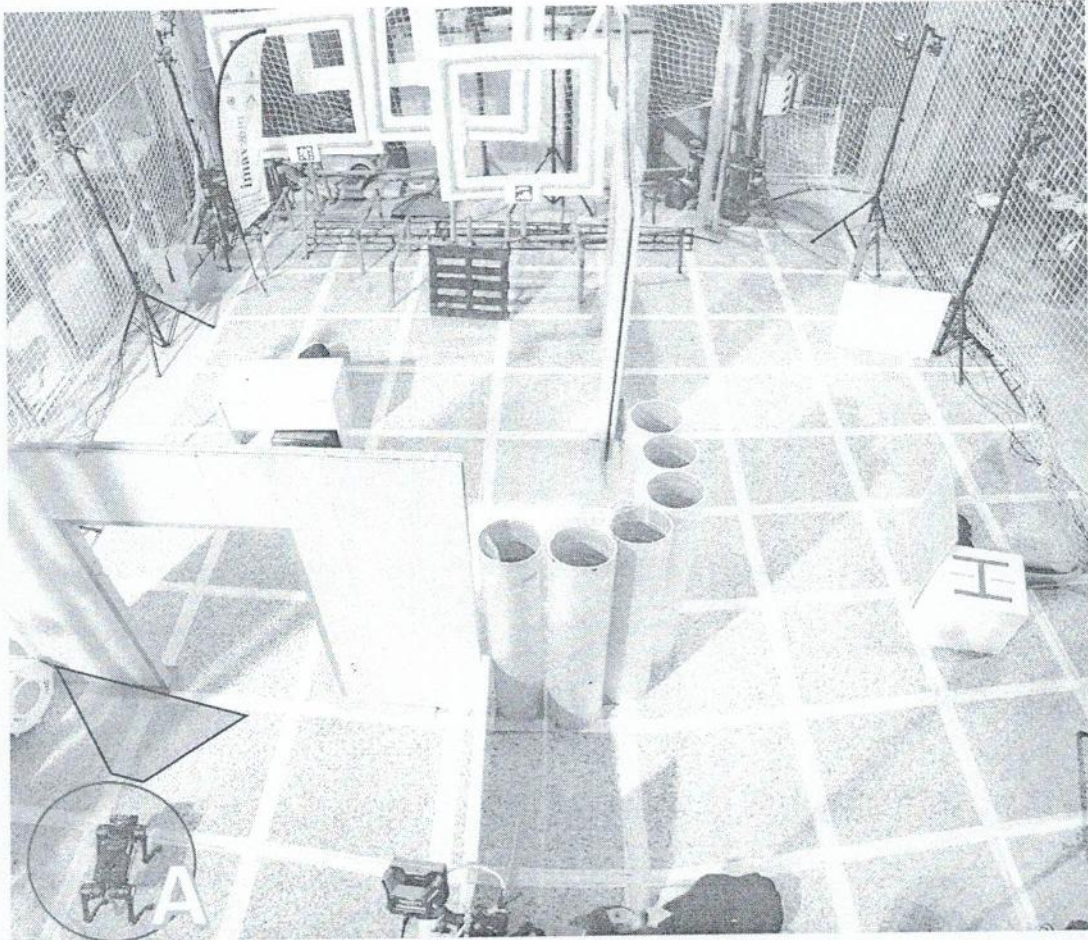


FRANCISCO JAVIER BADOSSA

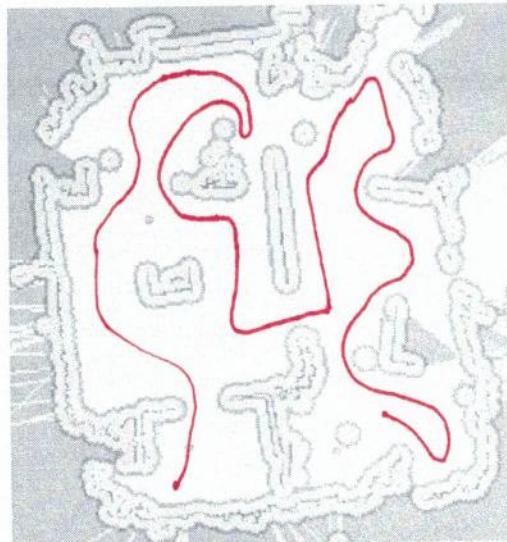
Francisco Javier Badosa

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer). starting from point "A" where the robot is located.



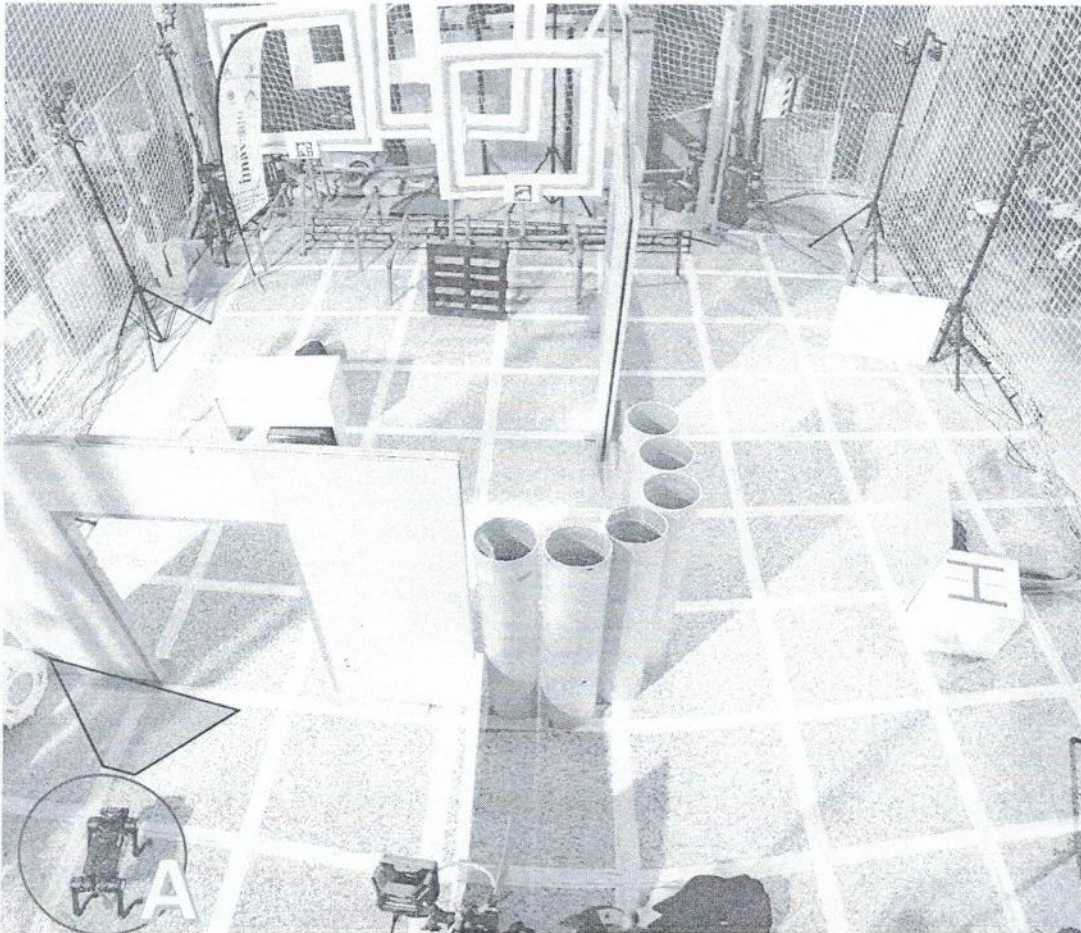
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



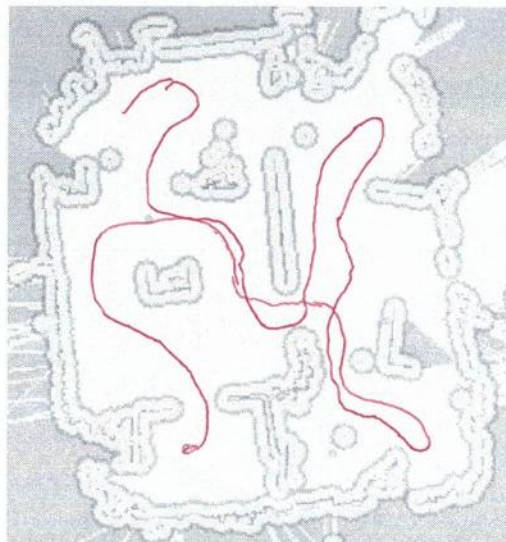
Paul Espinosu
[Handwritten signature]


Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



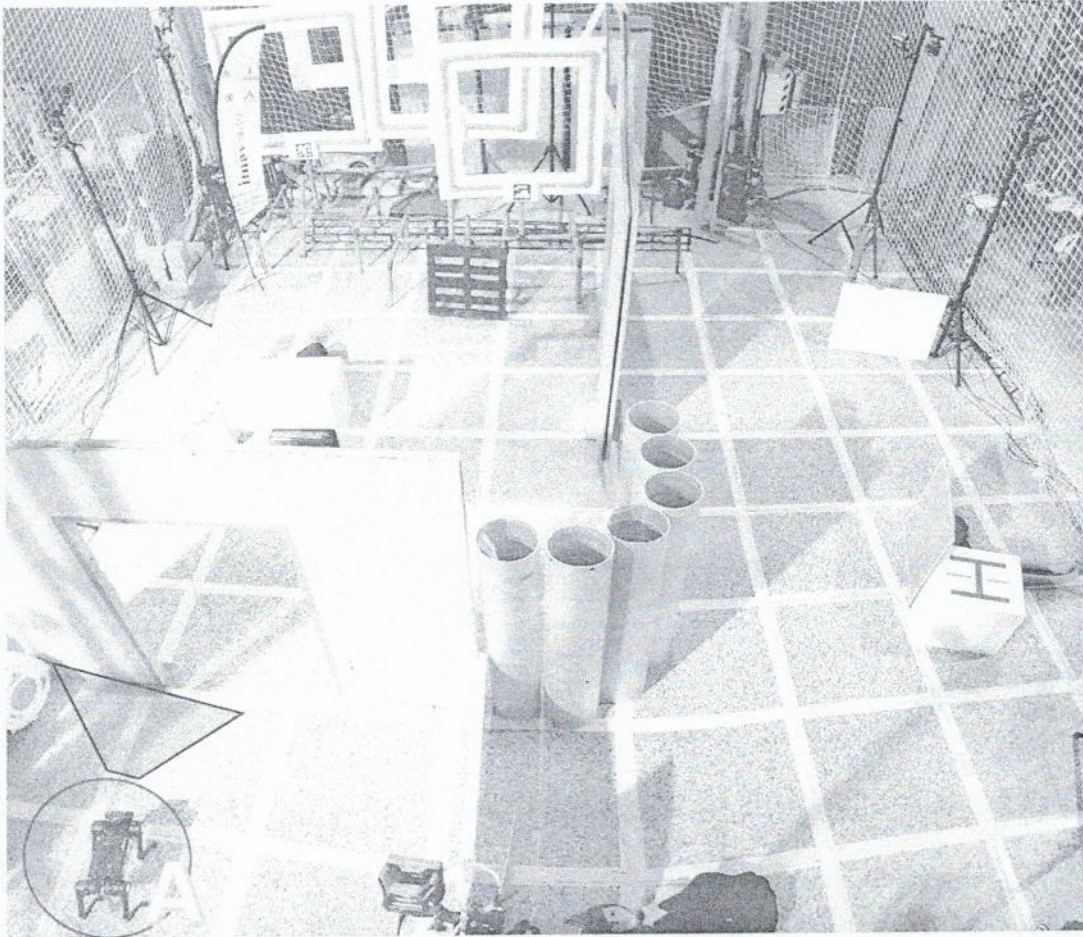
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



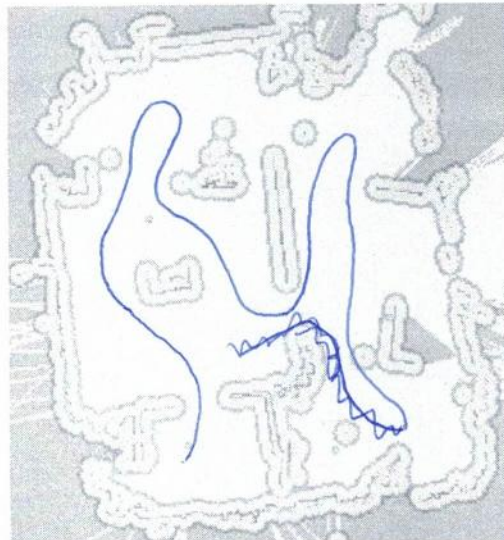
Guillermo Garcia 

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.

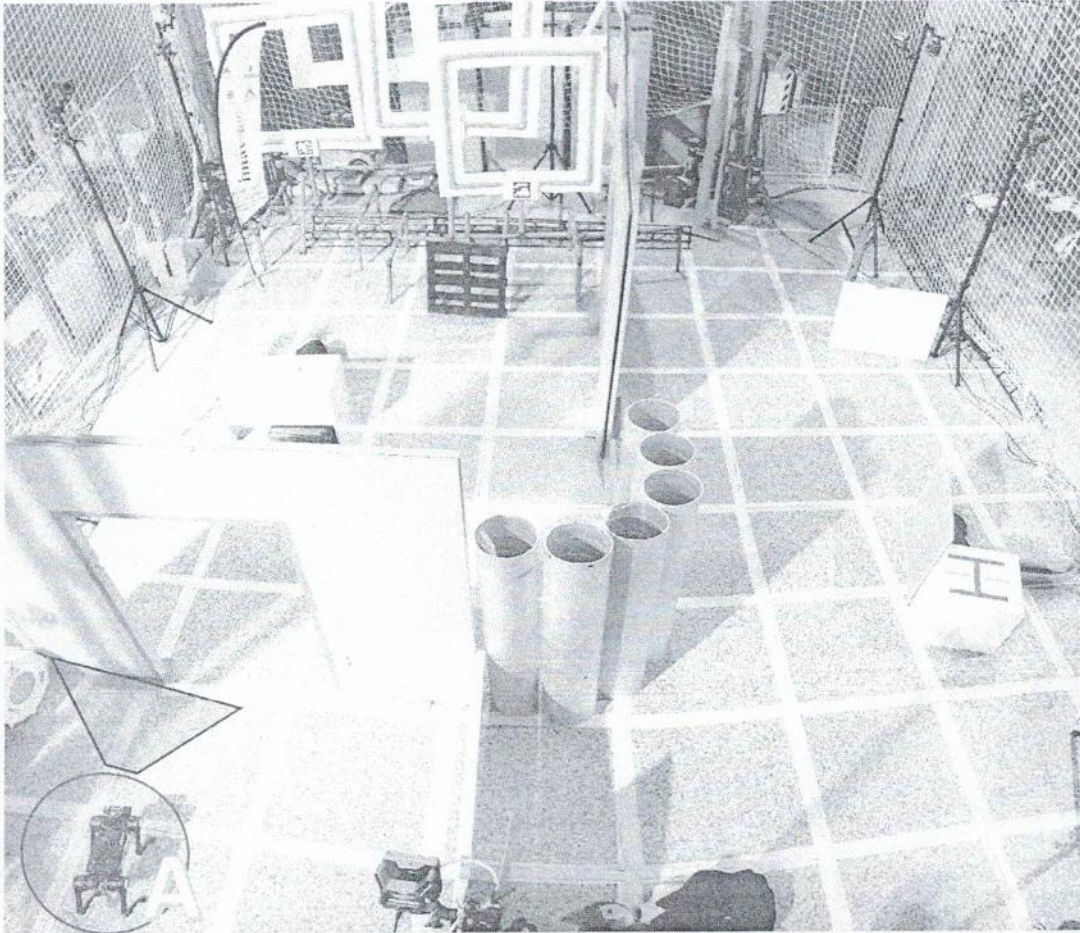


A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.

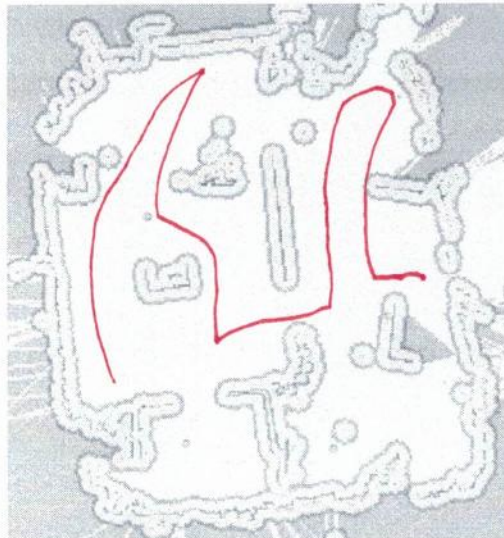


Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



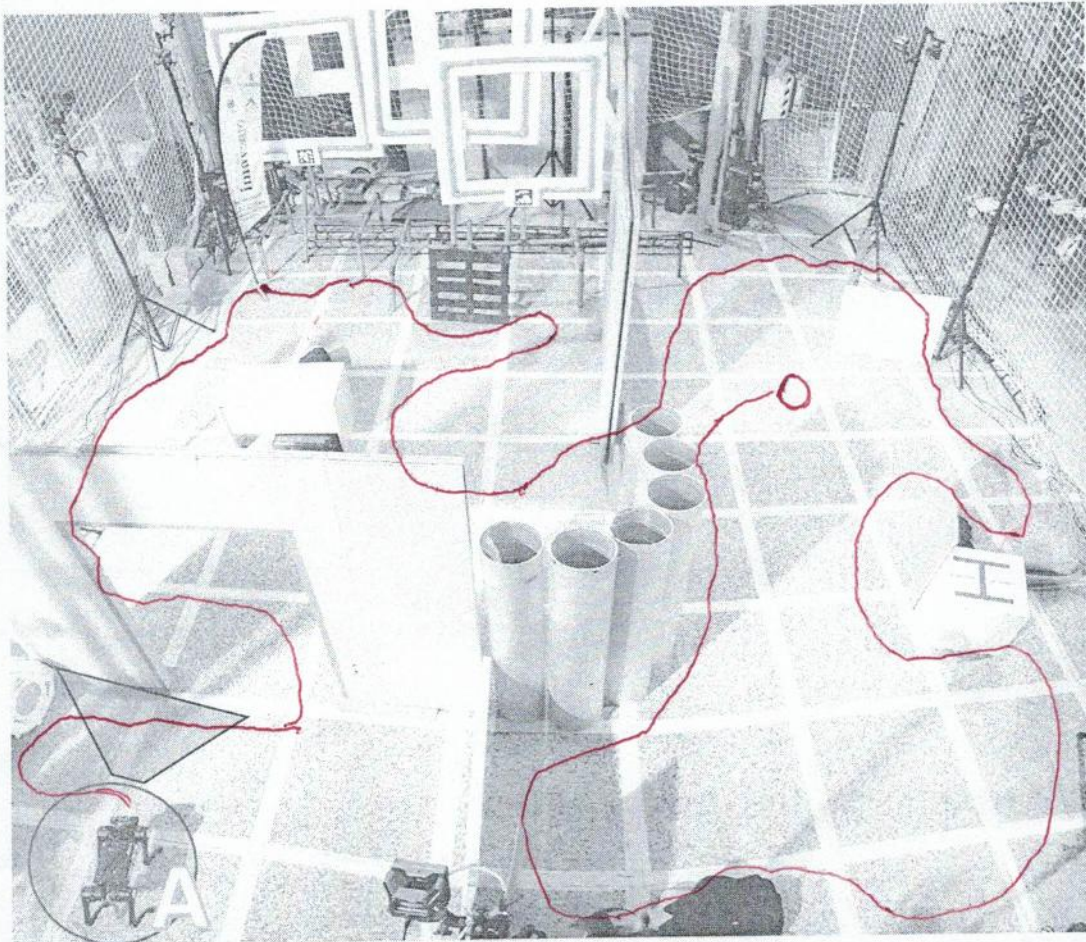
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



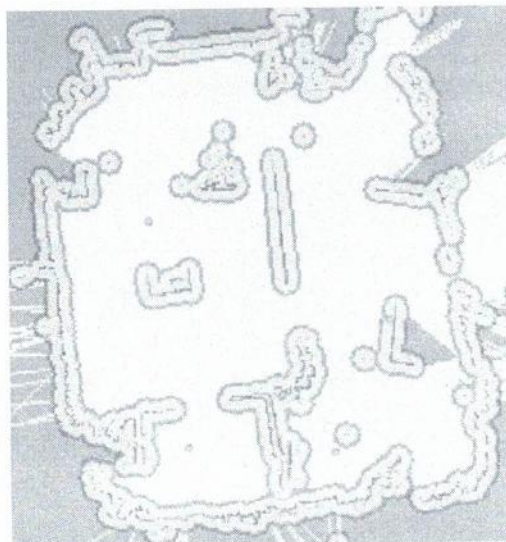
Kexin Zhang

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



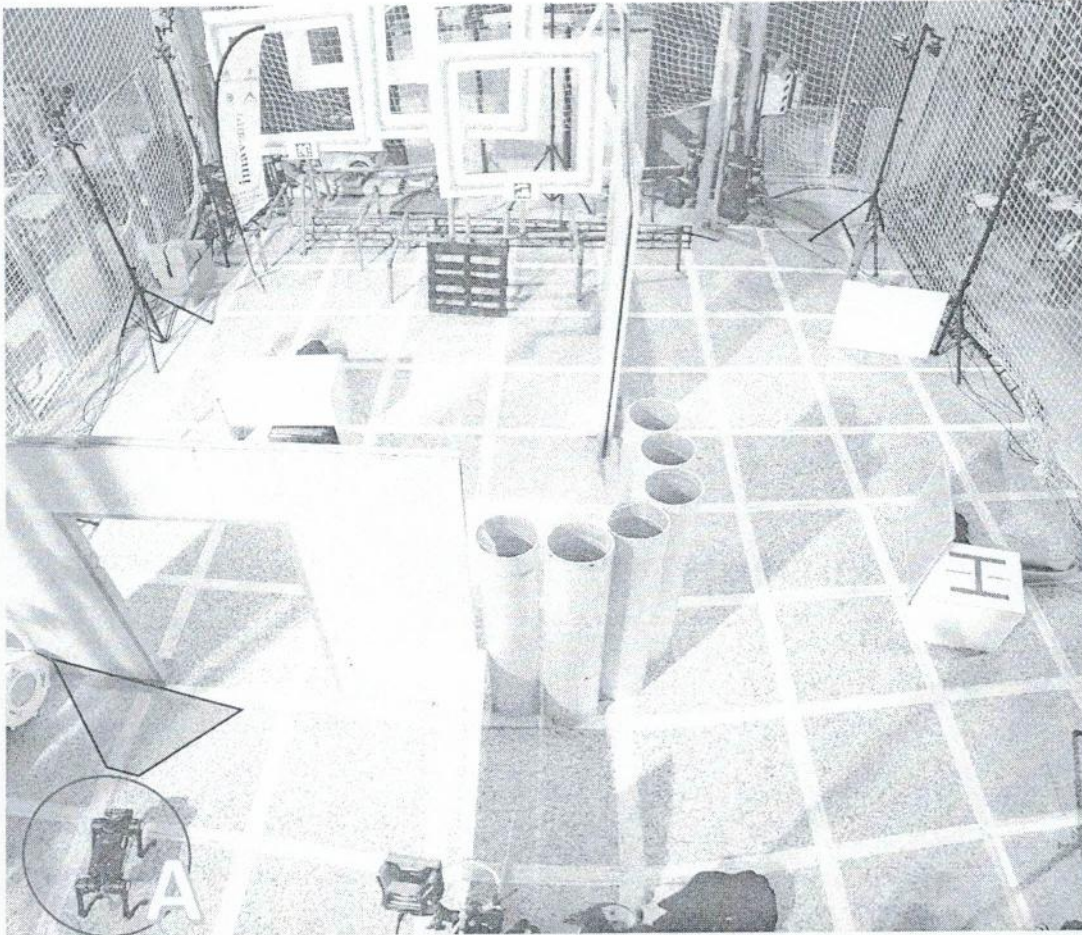
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



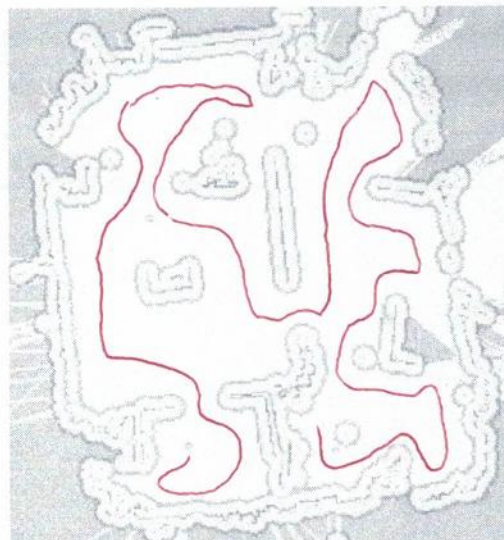
Nancy Barbosa

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.

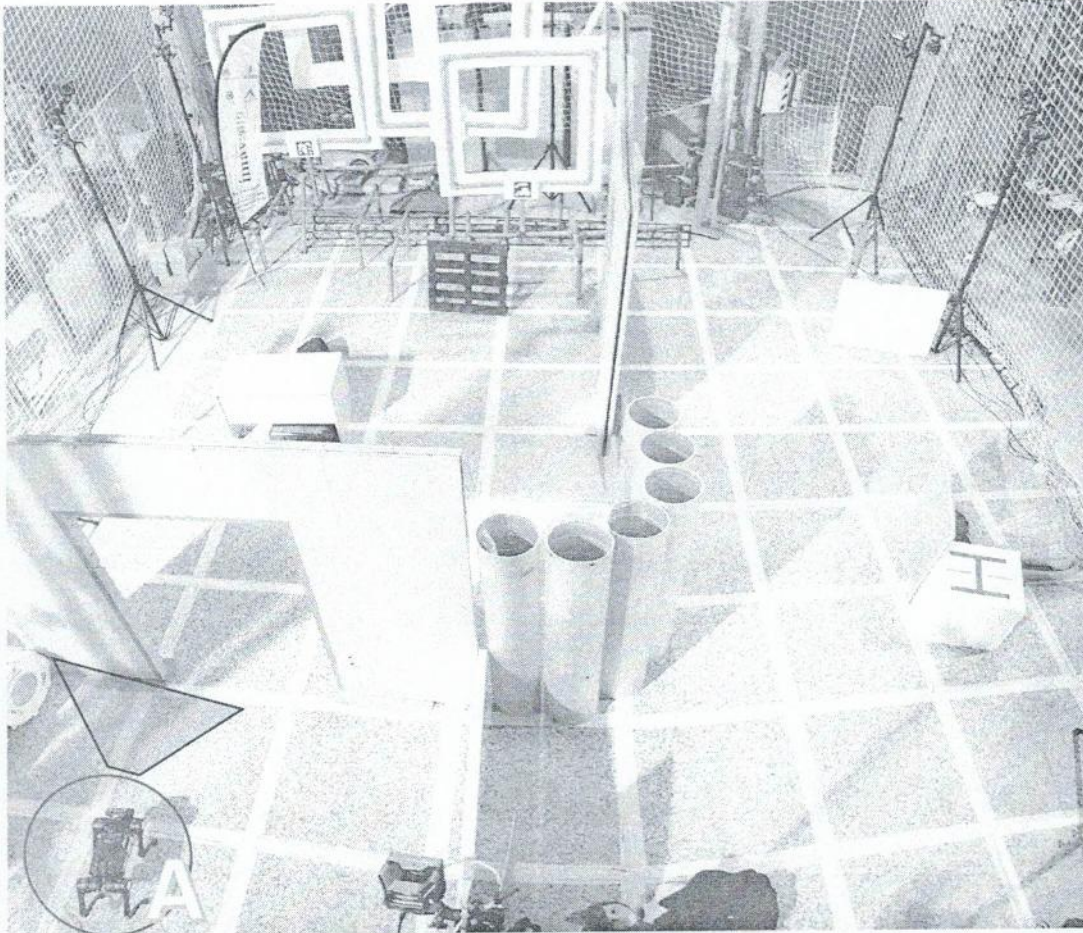


A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.

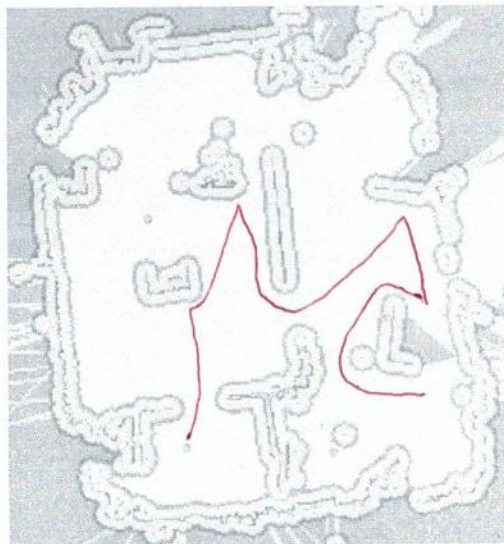


Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



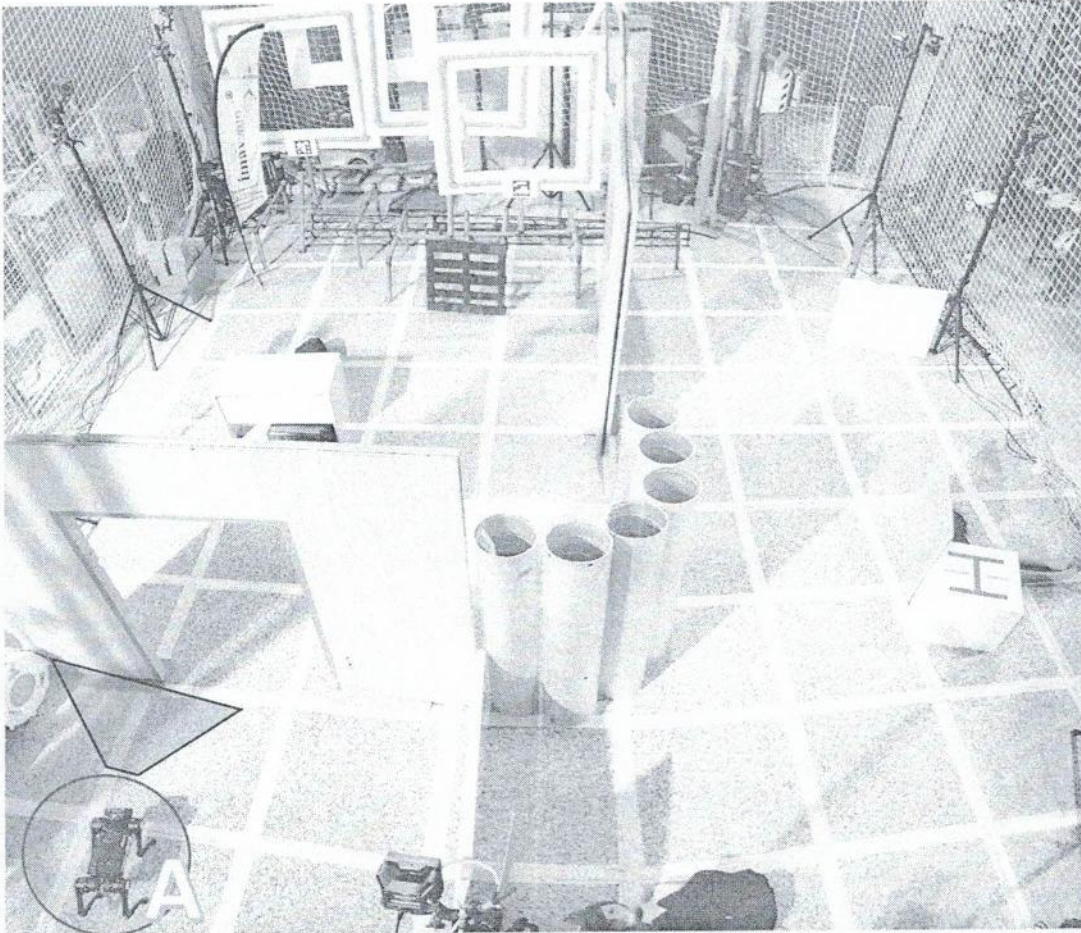
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



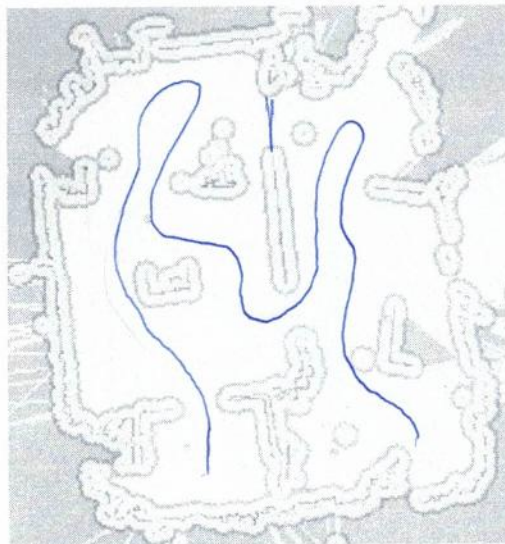
DAVID ORBEA
David Orbea

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer), starting from point "A" where the robot is located.



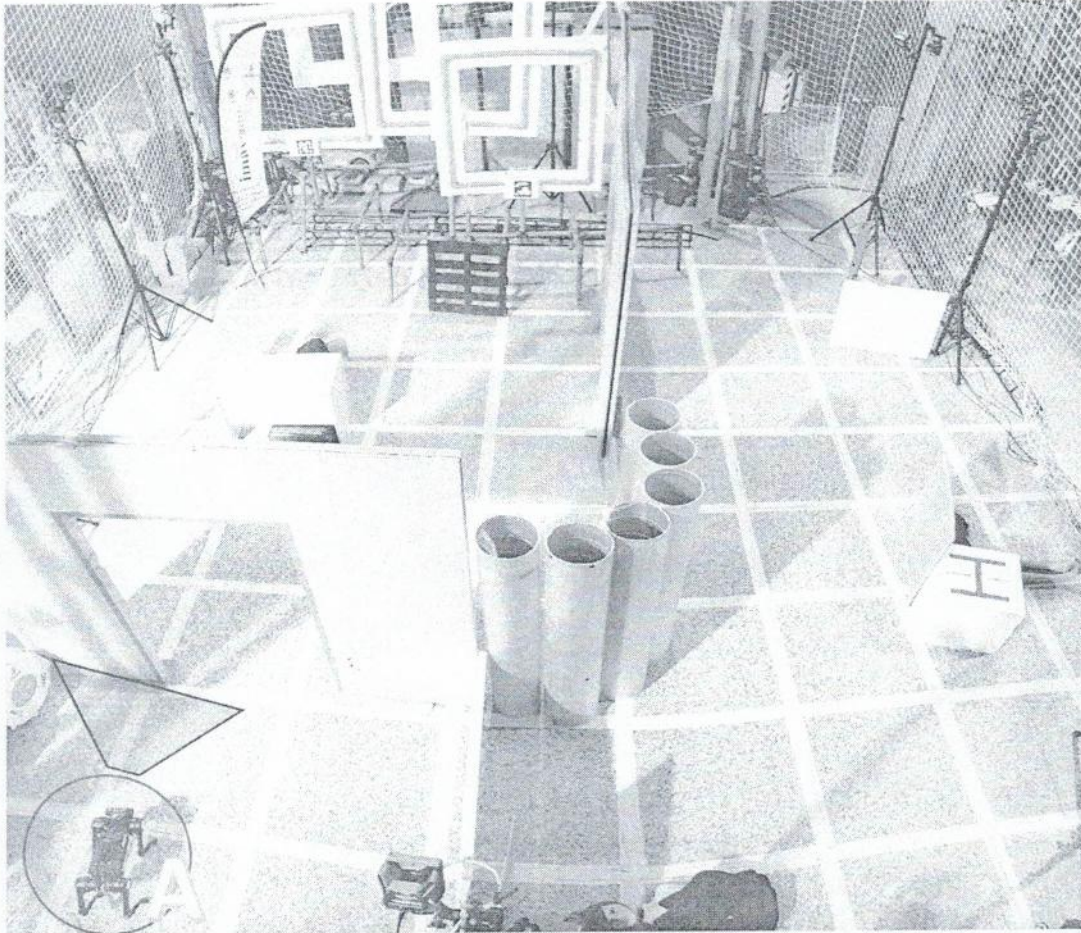
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



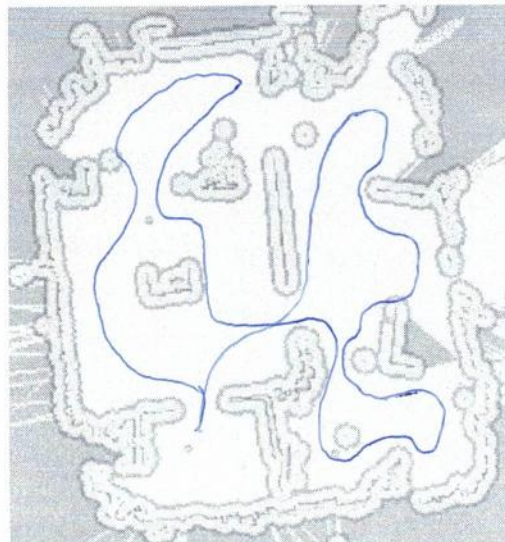
Juan Martinez Calvo
Juan Martinez

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer). starting from point "A" where the robot is located.



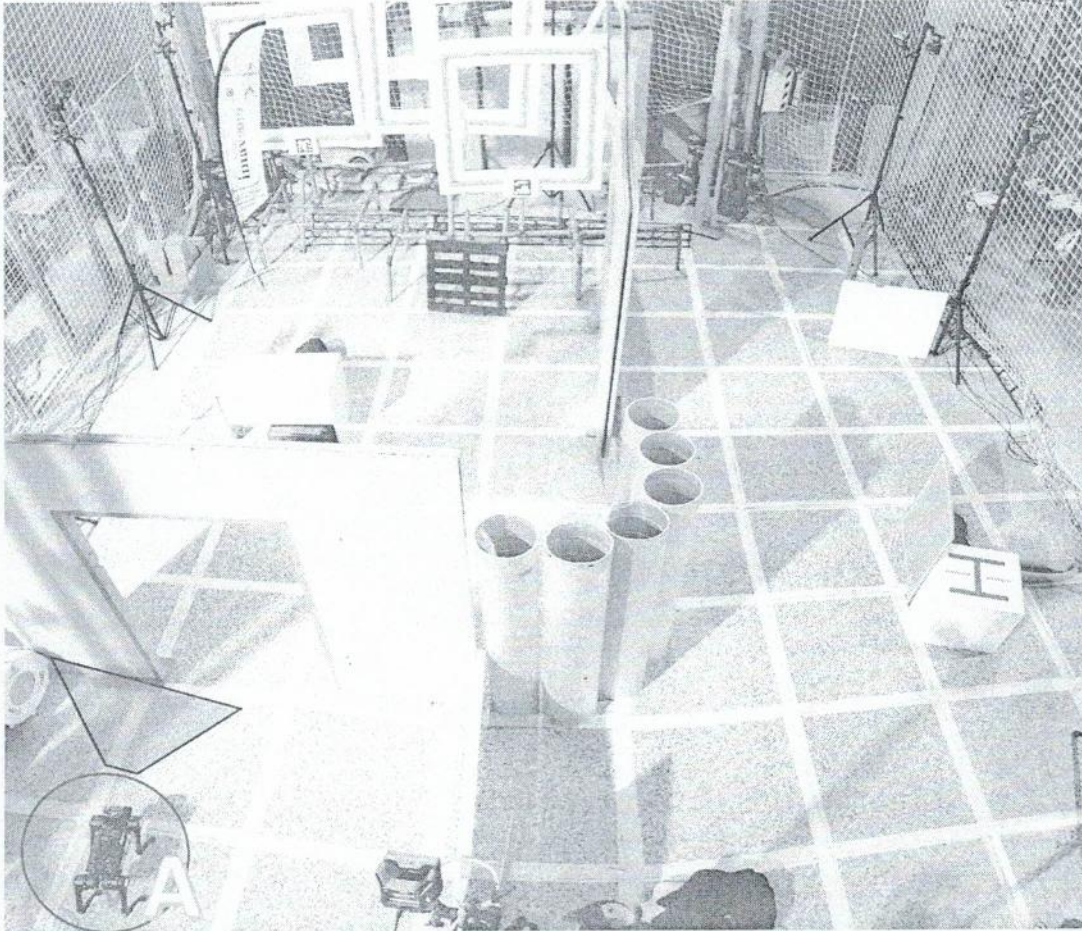
A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



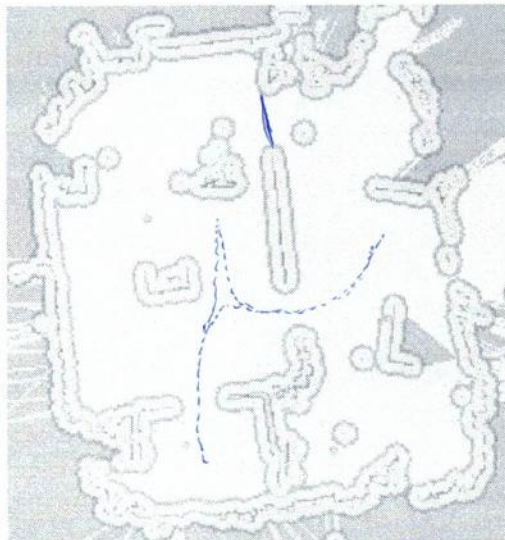
Virgilio Gonzalez
Virgilio Gonzalez

Experiment 1

Define the best exploration route to find the greatest number of potential victims in the unknown environment shown (from your perspective as a rescuer). starting from point "A" where the robot is located.



A reference of the 2D environment map generated by the robot's lidar is shown, after completing the exploration.



Santiago Urea
~~Santiago~~