## 1a.iii: Detailed Bullet Points (Technical, Structured)

* **Policy π Decomposition:**
  + Human agents w1​,w2​ execute t1​ and t3​ tasks along complementary path sequences.
  + Robotic agents r1​,r2​ execute all t2​ tasks concurrently via spatial partitioning.
* **Multi-Objective Optimization (Pareto Front P):**
  + P is the non-dominated set in the bi-criteria space (P(π),E[C]).
  + It defines the optimal performance boundary, minimizing E[C] subject to maximal P(π).
* **Optimal Policy πopt​ for P(π)≥0.91 (Solution 15):**
  + **System Reliability P(π):** 0.916
  + **Expected Cost E[C]:** 37.10
  + **Local Fault Tolerance Nmax​(ti​):** Budget is concentrated on high-risk t2​ tasks: t2​l5 is assigned Nmax​=9, t2​l9 is assigned Nmax​=8, and t2​l8b is assigned Nmax​=5.