### 1aii: Formal, Long, Single Coherent Paragraph

The planning system generated a precise, time-sequenced plan that assigns specific actions to each agent. The Human Worker (h1) is scheduled to execute both Electrical Installation tasks (t2\_ip2, t2\_ip1) consecutively at Room H before relocating to handle both instances of Plumbing Installation (t3\_bza at Room D and t3\_bzb at Room E). Concurrently, Robot r1 moves to Room F for Foundation preparation (t1\_msa), Robot r2 moves to Room G for its Foundation preparation (t1\_msb), and Robot r3 first completes Finishing work (t4\_se1) at Room J before transiting to Room I to execute the final Finishing work (t4\_wcp1). The **Pareto front** identifies the most efficient set of non-dominated solutions by mapping the critical trade-off between maximizing mission success probability and minimizing total mission cost, ensuring no solution exists that can improve one metric without compromising the other. To meet the minimum required success probability of 0.90, the plan utilizes the optimal solution with a **0.904 probability** and the lowest corresponding cost of **$48.101**. This cost-reliability trade-off is implemented by conservatively limiting the Human Worker (h1) to **one retry** for all four task instances while allocating robust retry capacity to the autonomous agents for higher-risk tasks, specifically **five retries** for Robot r3's t4\_se1 and **four retries** for Robot r2's t1\_msb, thereby maximizing reliability while controlling expenditure.