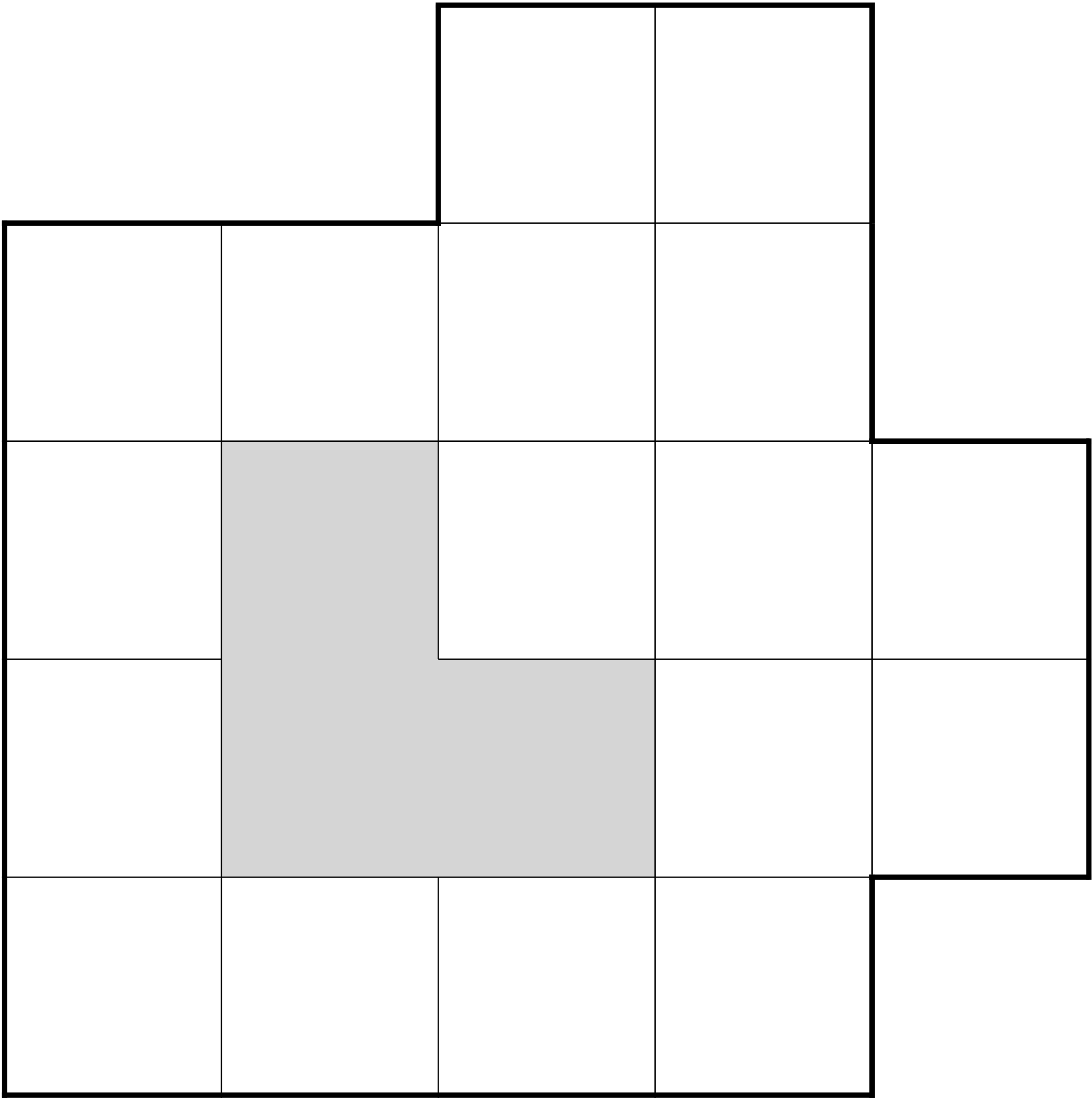
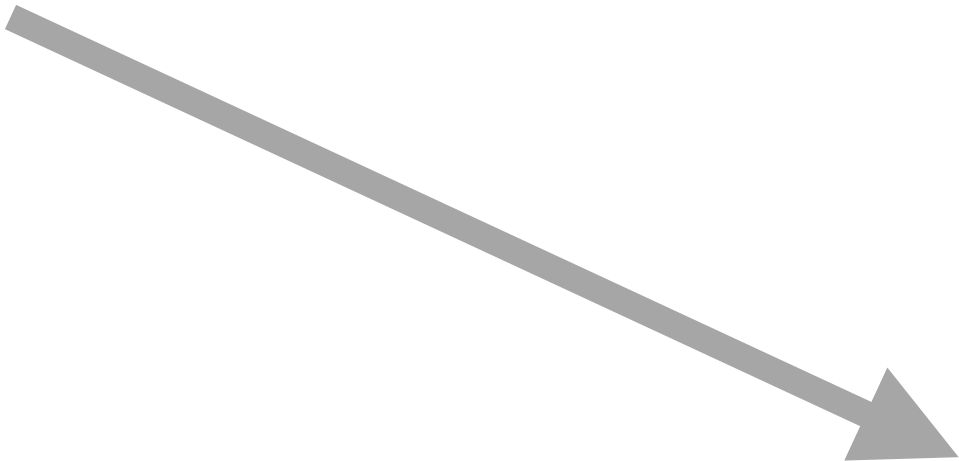




Multi-Agent Pathfinding [Stern+ SoCS-19]

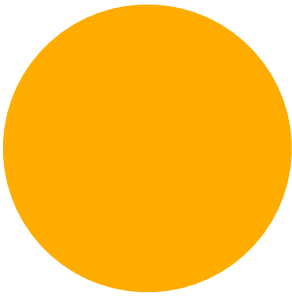
(MAPF)











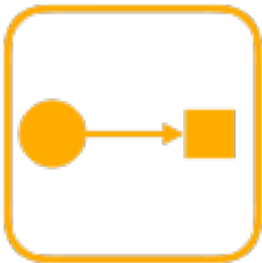


Input

- graph $G = (V, E)$
- agents' initial locations ●
- agents' goals ■

Output

- Conflict-free paths



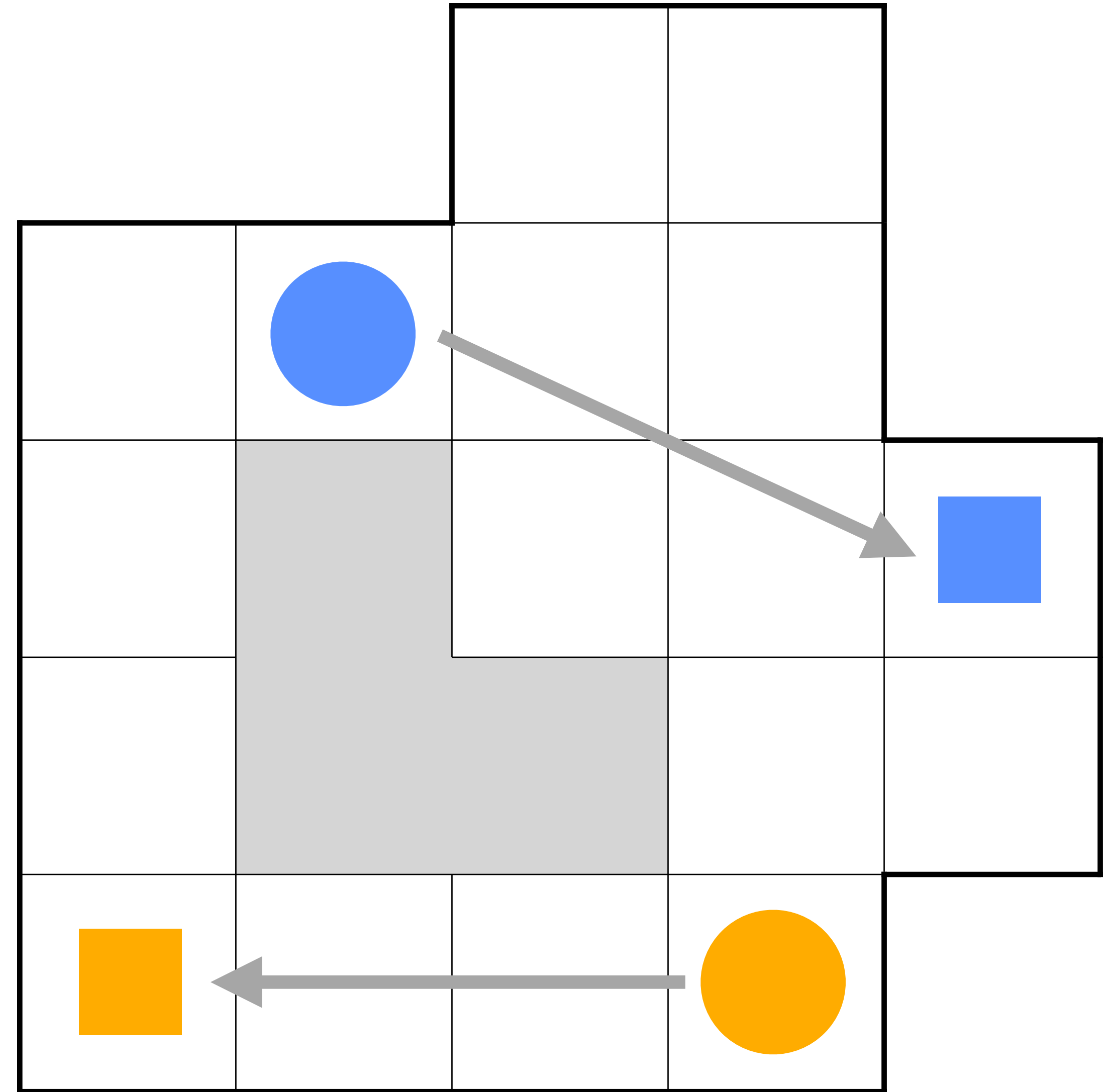
Multi-Agent Pathfinding^[Stern+ SoCS-19] (MAPF)

Input

- graph $G = (V, E)$
- agents' initial locations ●
- agents' goals ■

Output

- Conflict-free paths



Multi-Agent Pickup and Delivery^[Li+ AAAI-20] (MAPD)

Differences with respect to MAPF 

Input

- sequence of goals for each agent
e.g. for agent i with m goals:
 $\{\blacksquare_{i1}, \blacksquare_{i2}, \dots, \blacksquare_{im}\}$

Constraint

- Online (not all tasks are initially known)

