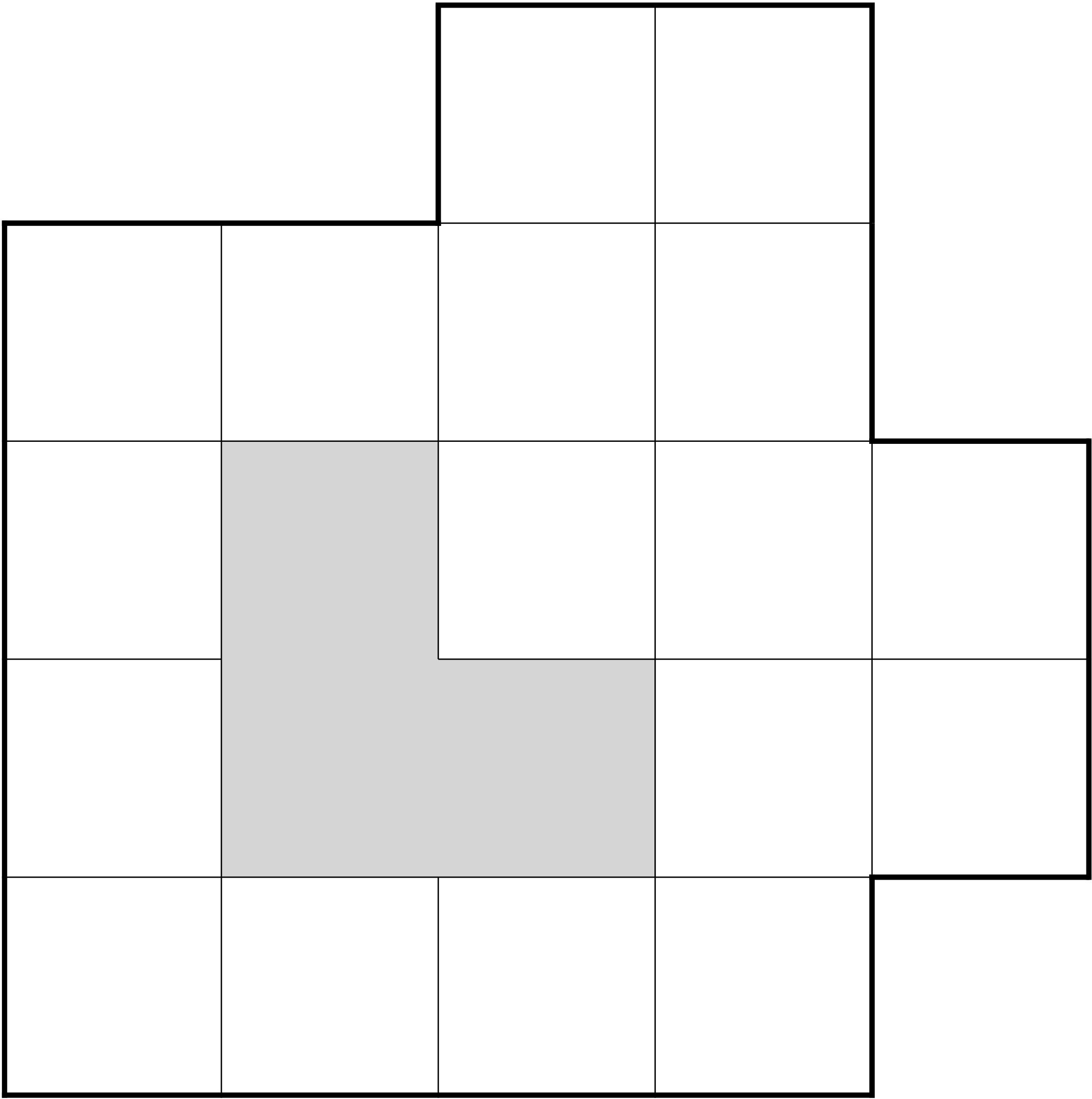
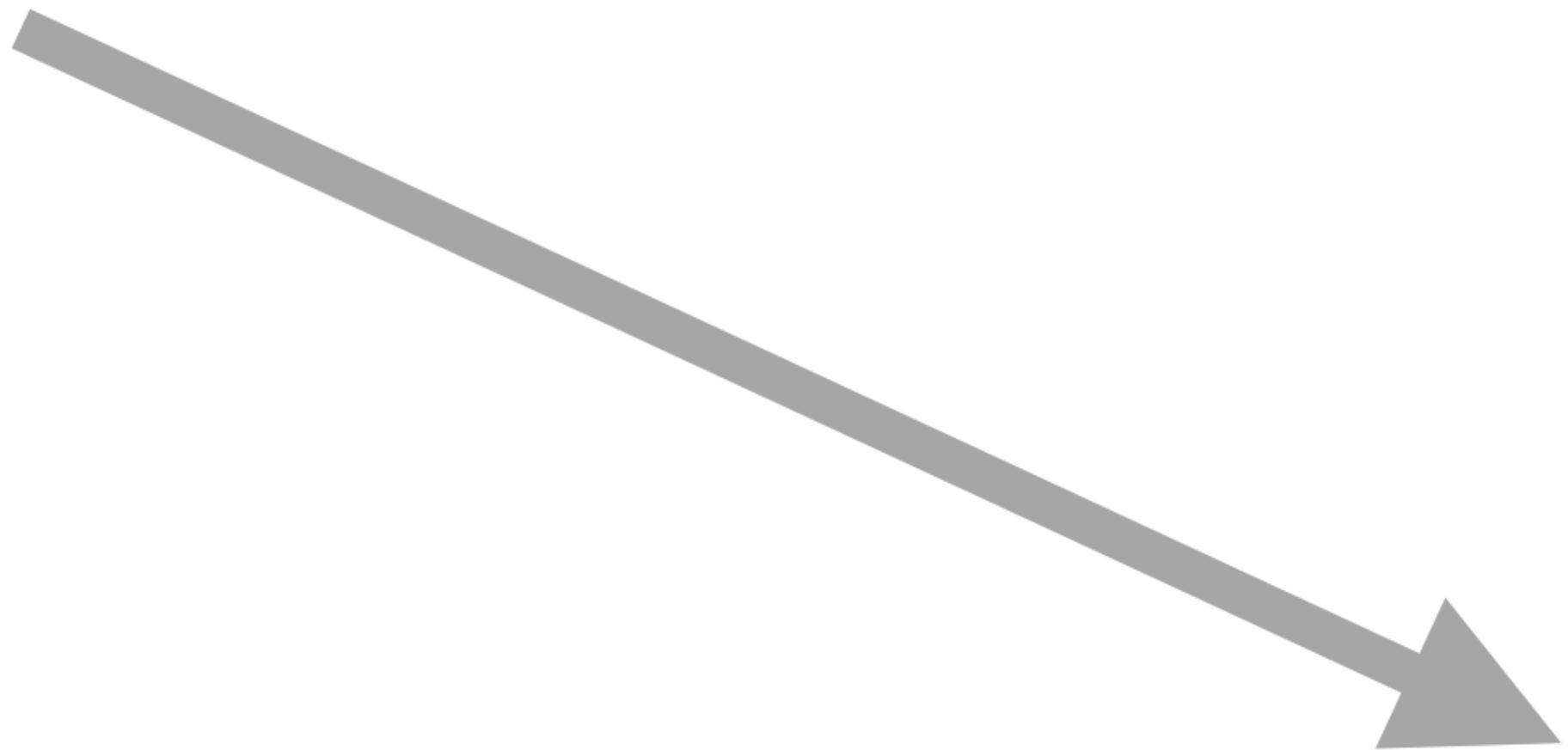
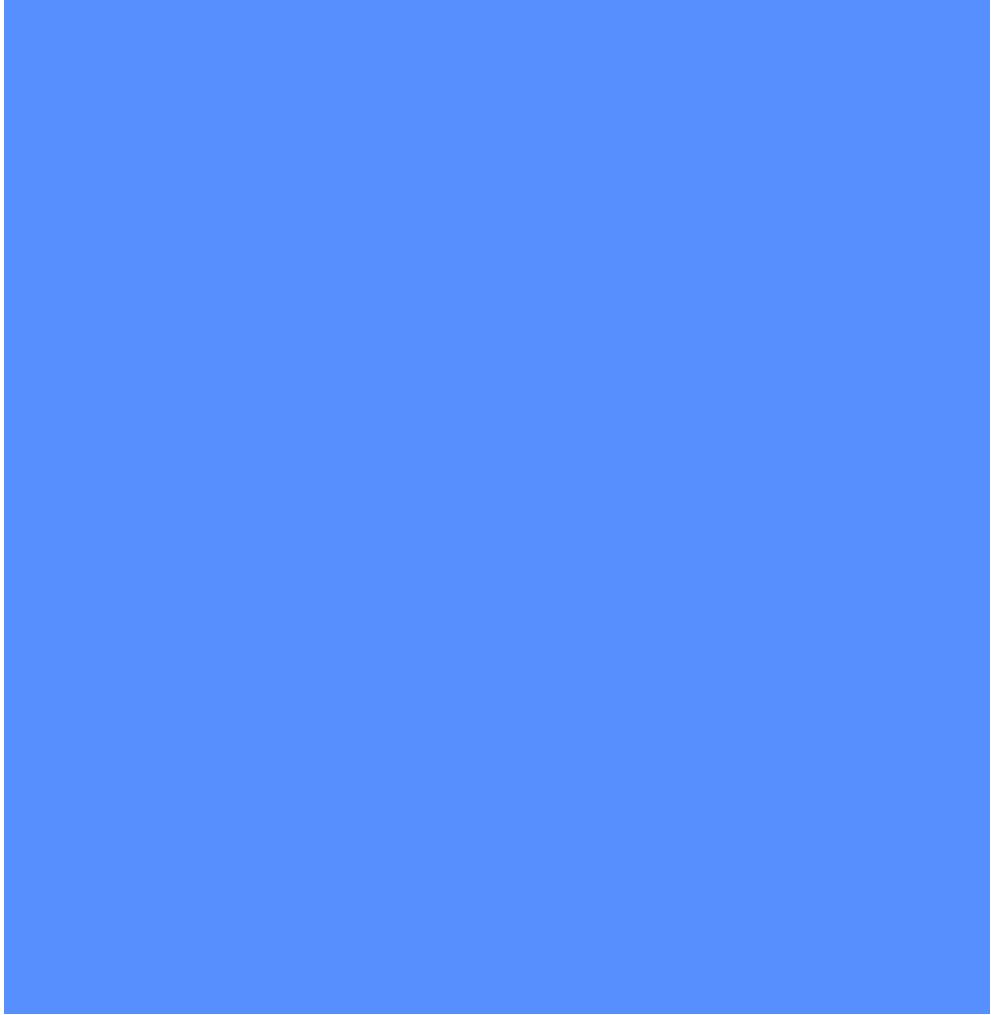


Multi-Agent Pathfinding^[Stern+ SoCS-19] (MAPF)

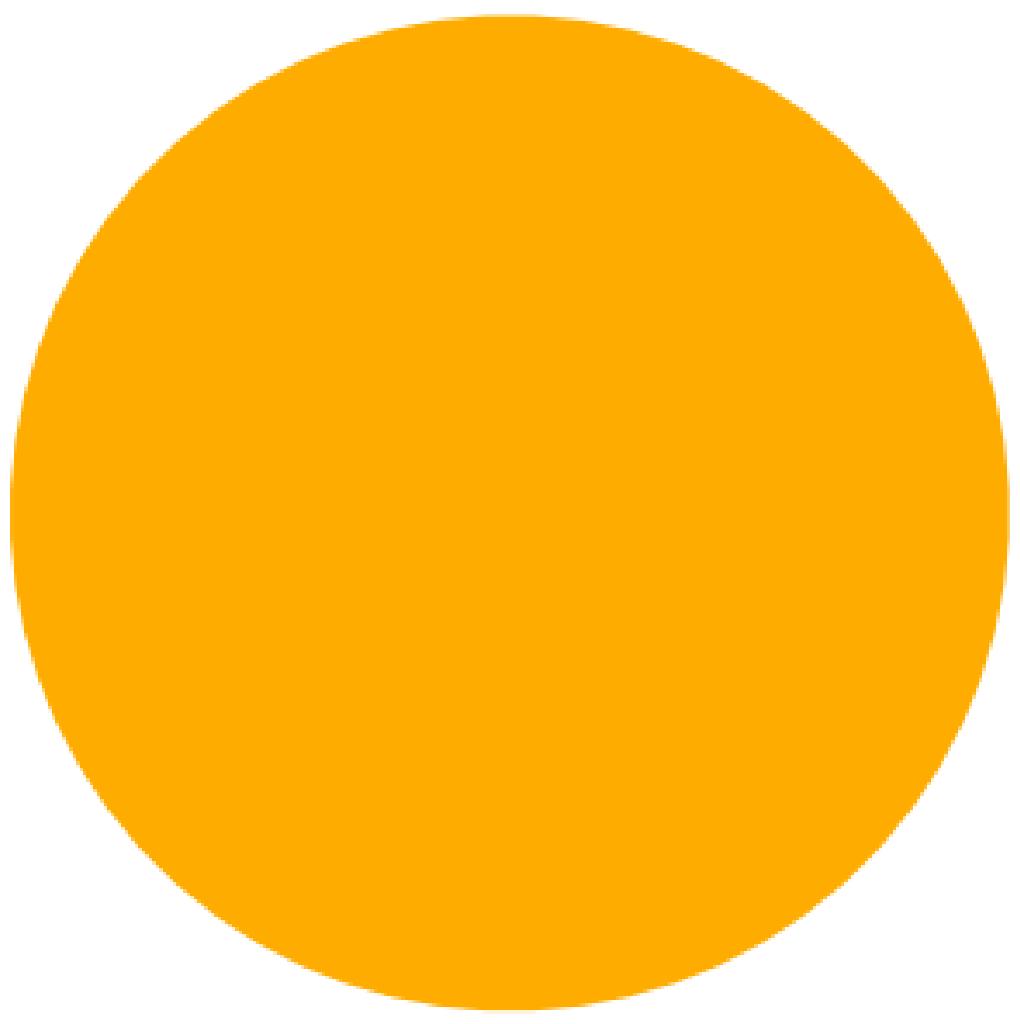












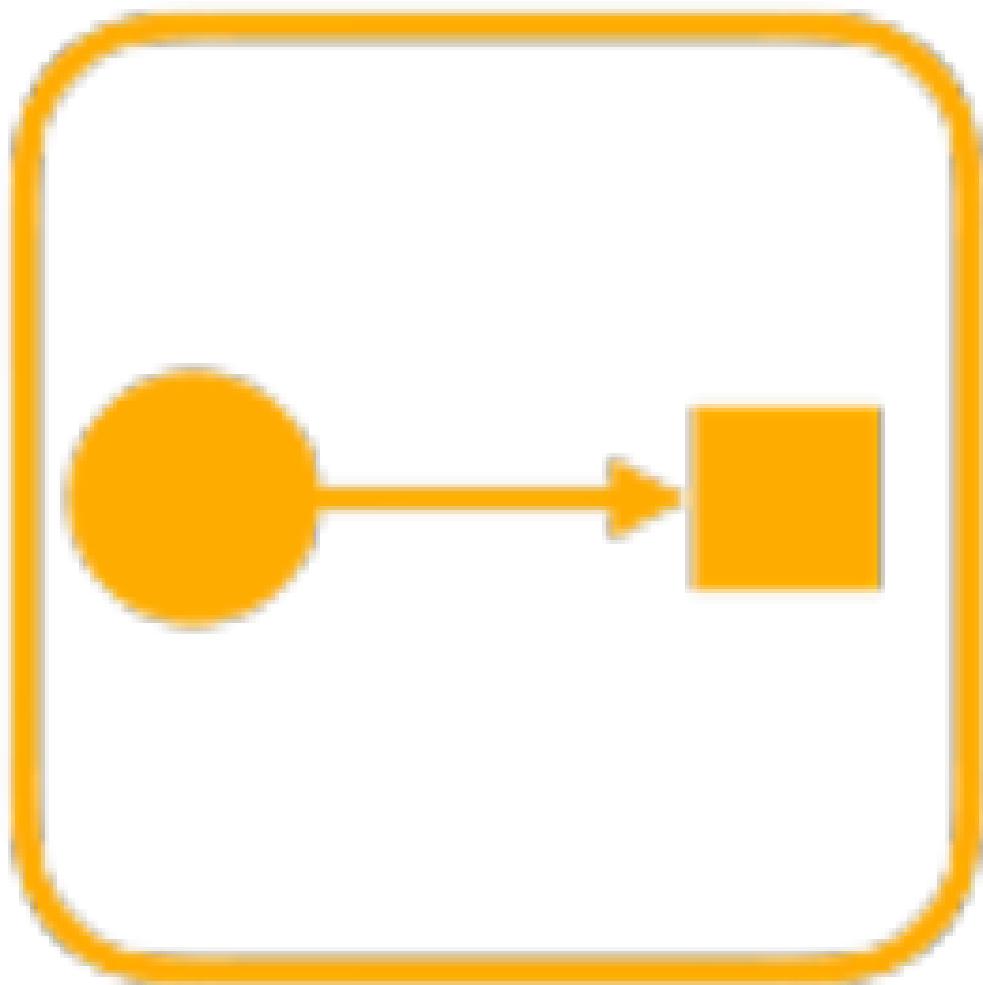


Input

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

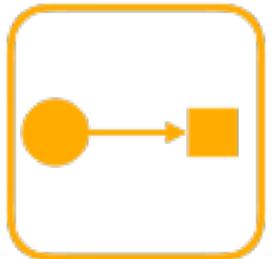
Output

- Conflict-free paths



Multi-Agent Pathfinding [Stern+ SoCS-19]

(MAPF)

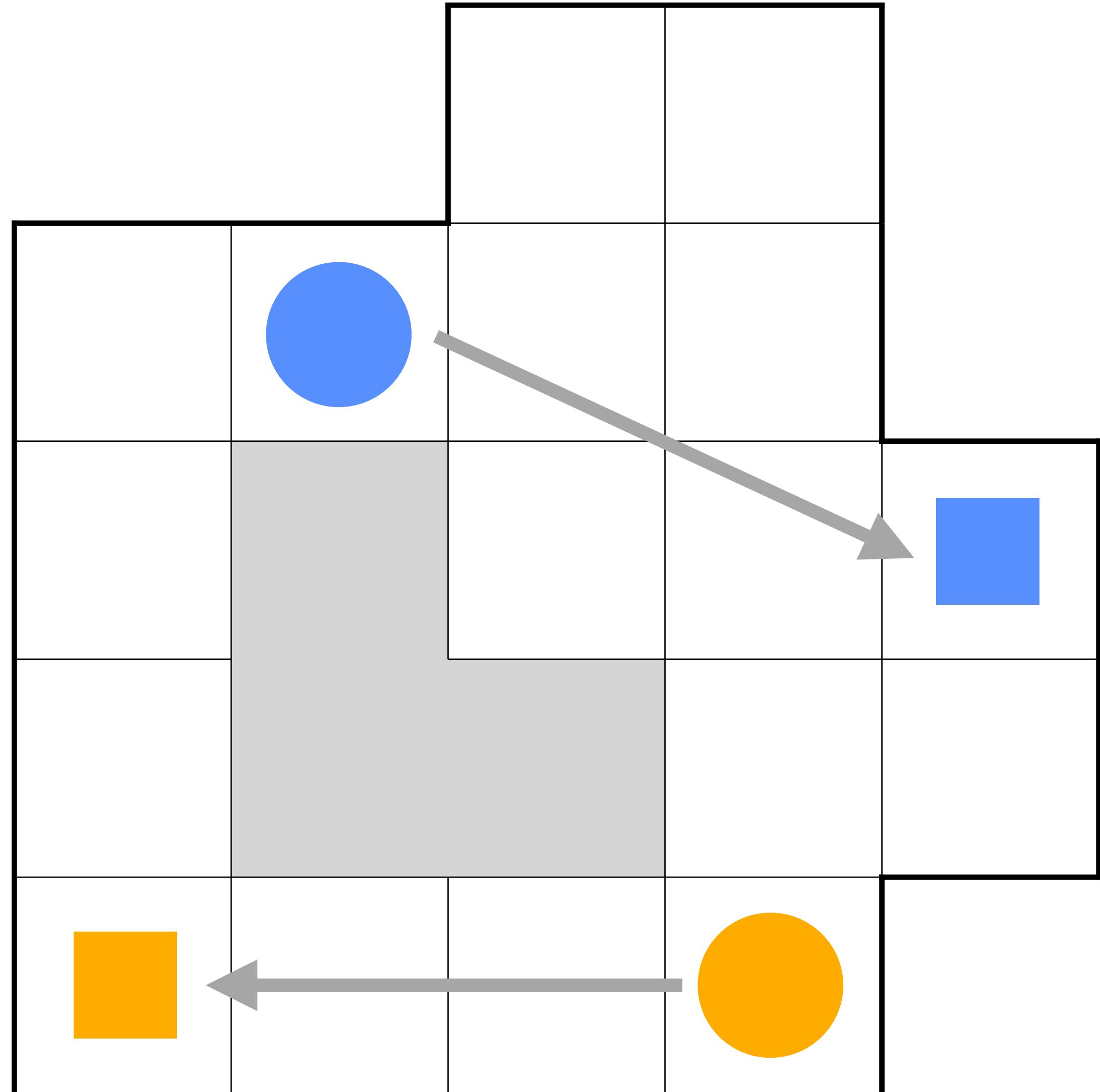


Input

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

Output

- Conflict-free paths

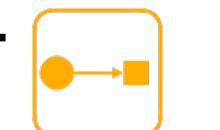


Multi-Agent Pickup and Delivery [Li+ AAAI-20]

(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)

