Table 1: List of Major Notations Used in the Paper

Notations	Descriptions
$\mathcal{G}(\mathcal{V}, \mathcal{E})$	the directed graph with nodes $\mathcal{V}$ and edges $\mathcal{E}$
$\mathcal{V}$	the set of nodes
$\mathcal{E}$	the set of edges
$\mathcal{C}$	the impact on whole team's probability of arriving on time
$\mathcal{R}$	the set of robots
$(\mathcal{O}, \mathcal{D})$	the origin-destination pair of corresponding robot
$\mathcal{T}$	time budget of task for corresponding robot
$\mathcal{I}$	the importance of task for corresponding robot
ϕ	the set denoting all the possible policies
λ_i	the weight of importance
$\mathcal{P}_i(\phi)$	the impact on each agent's probability of arriving on time
$\mathbb{H}(X)$	information entropy of the map
w_i	the word is indexed as i in the dictionary
$\boldsymbol{v_i}$	the center words
$\boldsymbol{u_i}$	the context words
e_{ij}	the attention coefficient of neighbours
W	the learnable weight matrix used for linear transformations
$\boldsymbol{a}$	a vector used to calculate the attention coefficient
$\mathcal{N}_i$	the set of neighbouring vertices of node v_i
α_{ij}	the normalized attention coefficient
$(\boldsymbol{h}_i', \boldsymbol{h}_i''$	feature representations
θ_{ij}	the parameter vector of policy
$\pi_{\boldsymbol{\theta}}(a \mid s)$	the policy under state s
$J_{\boldsymbol{\theta}}$	the objective function of our algorithm
$G(\tau)$	the cost function of robots
$J_{\mathbb{P}}$	the objective function of probability
$J_{\mathbb{H}}$	the objective function of information entropy