

Robot i



⋮

Robot 1

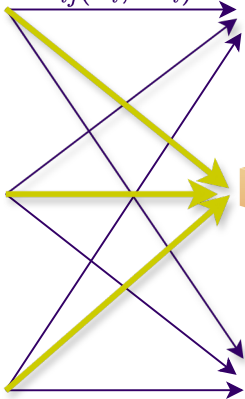


⋮

Robot N_u



$$c_{ij}(\mathbf{x}_i, \mathbf{x}_{-i})$$



Task j

⋮



Task 1

⋮



Task N_t