

Robot 1



...

Robot i 

...

Robot N_u 

	1	2	...	L_t
\mathbf{b}_1				
\mathbf{p}_1				

...

	1	2	...	L_t
\mathbf{b}_i				
\mathbf{p}_i				

...

	1	2	...	L_t
\mathbf{b}_{N_u}				
\mathbf{p}_{N_u}				

Available tasks



Task 1

...

Task j

...

Task N_t