

Robot i



⋮

Robot 1

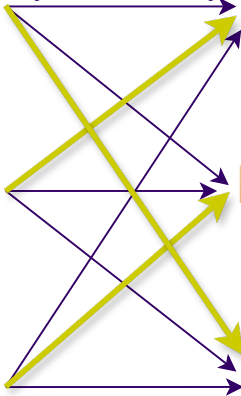


⋮

Robot N_u



$$c_{ij}(\mathbf{x}_i, \mathbf{p}_i) = c_{ij}$$



Task j

⋮



Task 1

⋮



Task N_t