

Robot i



⋮

Robot 1

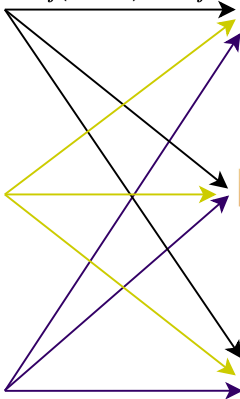


⋮

Robot N_u



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



Task j



⋮

Task 1



⋮

Task N_t

