**LISTED RESPONSE TO COMMENT/SUGGESTIONS FOR MINOR REVISION**

|  |  |  |  |
| --- | --- | --- | --- |
| ***No*** | ***Reviewer’s Comment/Suggestion*** | ***Author’s Comment*** | ***Action Taken\*\*\**** |
| 1 | *Reviewer 3:* In the 8th comment, page 17, the authors stated that "The path costs are updated as (15, 260), (18, 230) and (23, 200) where none of the path costs could dominate each other." However, the authors did not explain why the agent select the (18, 230). Please explain it. | Thanks for your comment. There was a typo on path costs and we updated them according to your comment. The path selection strategy works as follows; when there exist odd numbered non-dominated paths, the agent choose the median one (the paths are sorted ascending by first constraint). If there are *n* (even) numbered non-dominated paths, the agent chooses between *(n/2)th* and *((n/2)+1)th* paths randomly. This ad-hoc strategy can be changed according to application domain. | No change was done on the manuscript. |
| 2 | *Editor-in Chief:* I noticed that there is NO reference from this very journal. To establish a close tie with this publication, we would appreciate if you could identify and add a few relevant references published in the transactions in recent years, if there are any and there is space in the manuscript, for the best interest of the authors as well as the journal. | Thanks for your suggestion. Following entitled references are added. Also citations in bibtex format are given in Appendix.   * A Multirobot Path-Planning Strategy for Autonomous Wilderness Search and Rescue * Dynamic Task Assignment and Path Planning of Multi-AUV System Based on an Improved Self-Organizing Map and Velocity Synthesis Method in Three-Dimensional Underwater Workspace * Incremental Multi-Scale Search Algorithm for Dynamic Path Planning With Low Worst-Case Complexity | Mentioned references are added on Section I. |

**APPENDIX**

**BibTeX of added Citations:**

@ARTICLE{Macwan:2014,

author={Macwan, A. and Vilela, J. and Nejat, G. and Benhabib, B.},

journal={Cybernetics, IEEE Transactions on},

title={A Multirobot PathPlanning Strategy for Autonomous Wilderness Search and Rescue},

year={2014},

month={},

volume={PP},

number={99},

pages={11},

keywords={Interpolation;Optimization;Probabilistic logic;Probability density function;Robot kinematics;Robot sensing systems;Multirobot coordination (MRC);pathplanning;wilderness search and rescue (WiSAR)},

doi={10.1109/TCYB.2014.2360368},

ISSN={21682267},

}

@ARTICLE{Daqi:2013,

author={Daqi Zhu and Huan Huang and Yang, S.X.},

journal={Cybernetics, IEEE Transactions on},

title={Dynamic Task Assignment and Path Planning of MultiAUV System Based on an Improved SelfOrganizing Map and Velocity Synthesis Method in ThreeDimensional Underwater Workspace},

year={2013},

month={April},

volume={43},

number={2},

pages={504514},

keywords={autonomous underwater vehicles;mobile robots;multi-robot systems;neurocontrollers;path planning;robot dynamics;self-organising feature maps;velocity control;3D underwater workspace;AUV control;SOM neural network;SOM neuron network;autonomous underwater vehicle;dynamic task assignment;energy sufficiency;multiAUV system;path planning;self-organizing map;threedimensional underwater workspace;variable ocean current;velocity synthesis method;workload balance;Heuristic algorithms;Neurons;Oceans;Path planning;Robots;Vehicle dynamics;Vehicles;3D workspace;Dynamic task assignment;multiple autonomous underwater vehicle (AUV) (multiAUV) system;selforganizing map (SOM);timevarying ocean current;velocity synthesis},

doi={10.1109/TSMCB.2012.2210212},

ISSN={21682267},

}

@ARTICLE{Yibiao:2011,

author={Yibiao Lu and Huo, X. and Arslan, O. and Tsiotras, P.},

journal={Systems, Man, and Cybernetics, Part B: Cybernetics, IEEE Transactions on},

title={Incremental Multi-Scale Search Algorithm for Dynamic Path Planning With Low Worst-Case Complexity},

year={2011},

month={Dec},

volume={41},

number={6},

pages={1556-1570},

keywords={computational complexity;graph theory;path planning;search problems;VLSI design;computational complexity;dynamic shortest path planning problems;edge weights;graph;incremental multiscale search algorithm;lifelong planning A\* algorithm;low worst case complexity;multiscale environment representation;robot navigation;transportation;Algorithm design and analysis;Complexity theory;Heuristic algorithms;Mobile robots;Partitioning algorithms;Path planning;$hbox{A}^{ast}$ algorithm;$hbox{LPA}^{ast}$ algorithm;beamlet-like structure;dynamic programming;path-planning;quadtrees},

doi={10.1109/TSMCB.2011.2157493},

ISSN={1083-4419},

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