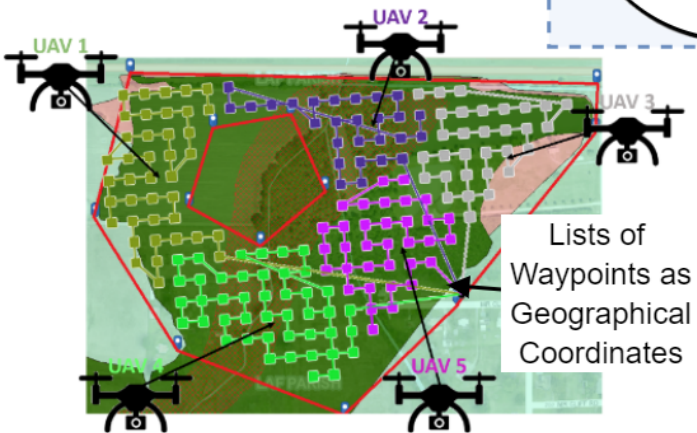


Step 1: User Input

Area & Priority Selection



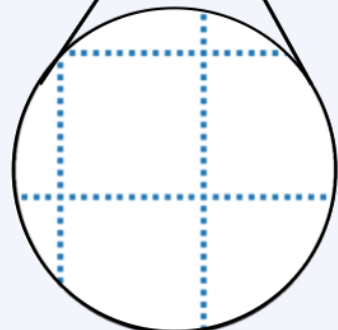
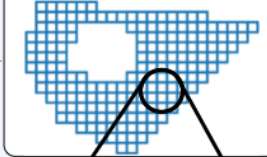
Number of Robots



Lists of
Waypoints as
Geographical
Coordinates

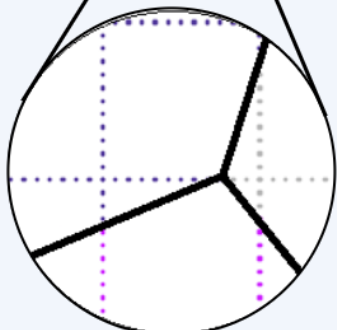
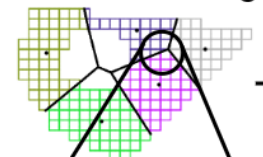
Step 2: Discretization

Discretization



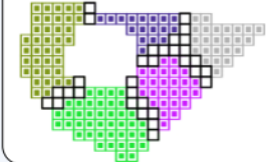
Step 3: Area Partitioning

Area Partitioning

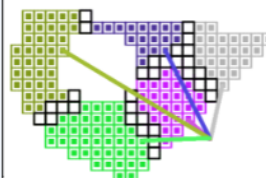


Step 4: Auctioning of Conflict Cells

Conflict Identification



State Bias Factor



Conflict Resolution



Step 5: Path Planning

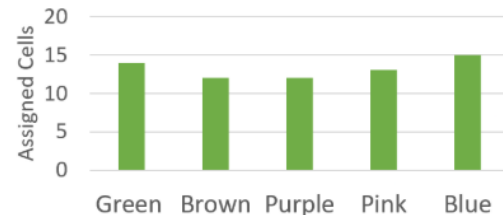
Regular Assignment



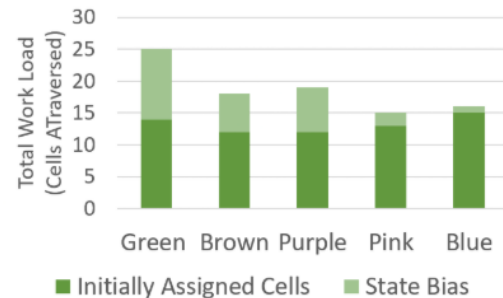
Priority Assignment



Work Load Distribution After Initial Partitioning



Work Load Distribution After Accounting for Robot States



Work Load Distribution After Biased Conflict Resolution

