

REFERENCES

- [1] M. Barer, G. Sharon, R. Stern, and A. Felner. 2014. Suboptimal variants of the conflict-based search algorithm for the multi-agent pathfinding problem. In *SoCS*.
- [2] X. Chen and P. Van Beek. 2001. Conflict-directed backjumping revisited. *Journal of Artificial Intelligence Research* 14 (2001), 53–81.
- [3] L. Cohen, G. Wagner, D. Chan, H. Choset, N. Sturtevant, S. Koenig, and T. K. S. Kumar. 2018. Rapid randomized restarts for multi-agent path finding solvers. In *SoCS*.
- [4] B. de Wilde, A. W. ter Mors, and C. Witteveen. 2013. Push and rotate: Cooperative multi-agent path planning. In *AAMAS*. 87–94.
- [5] E. Erdem, D. G. Kisa, U. Oztok, and P. Schueller. 2013. A general formal framework for pathfinding problems with multiple agents. In *AAAI*. 290–296.
- [6] M. Goldenberg, A. Felner, R. Stern, G. Sharon, N. R. Sturtevant, R. C. Holte, and J. Schaeffer. 2014. Enhanced partial expansion A^* . *Journal of Artificial Intelligence Research* 50 (2014), 141–187.
- [7] M. M. Khorshid, R. C. Holte, and N. R. Sturtevant. 2011. A polynomial-time algorithm for non-optimal multi-agent pathfinding. In *SoCS*.
- [8] J. Li, P. Surynek, A. Felner, H. Ma, T. K. S. Kumar, and S. Koenig. 2019. Multi-agent path finding for large agents. In *AAAI*.
- [9] R. Luna and K. E. Bekris. 2011. Push and swap: Fast cooperative path-finding with completeness guarantees. In *IJCAI*. 294–300.
- [10] H. Ma, G. Wagner, A. Felner, J. Li, T. K. S. Kumar, and S. Koenig. 2018. Multi-agent path finding with deadlines. In *IJCAI*. 417–423.
- [11] H. Ma, J. Yang, L. Cohen, T. K. S. Kumar, and S. Koenig. 2017. Feasibility study: Moving non-homogeneous teams in congested video game environments. In *AIIDE*. 270–272.
- [12] R. Morris, C. Pasareanu, K. Luckow, W. Malik, H. Ma, T. K. S. Kumar, and S. Koenig. 2016. Planning, scheduling and monitoring for airport surface operations. In *AAAI-16 Workshop on Planning for Hybrid Systems*.
- [13] G. Sharon, R. Stern, A. Felner, and N. R. Sturtevant. 2015. Conflict-based search for optimal multi-agent pathfinding. *Artificial Intelligence* 219 (2015), 40–66.
- [14] D. Silver. 2005. Cooperative pathfinding. In *AIIDE*. 117–122.
- [15] T. S. Standley. 2010. Finding optimal solutions to cooperative pathfinding problems. In *AAAI*. 173–178.
- [16] N. R. Sturtevant and M. Buro. 2006. Improving collaborative pathfinding using map abstraction. In *AIIDE*. 80–85.
- [17] P. Surynek. 2009. A novel approach to path planning for multiple robots in bi-connected graphs. In *ICRA*. 3613–3619.
- [18] P. Surynek. 2012. Towards optimal cooperative path planning in hard setups through satisfiability solving. In *PRICAI*. 564–576.
- [19] P. Surynek. 2015. Reduced time-expansion graphs and goal decomposition for solving cooperative path finding sub-optimally. In *IJCAI*. 1916–1922.
- [20] M. M. Veloso, J. Biswas, B. Coltin, and S. Rosenthal. 2015. CoBots: Robust symbiotic autonomous mobile service robots. In *IJCAI*. 4423.
- [21] K. Wang and A. Botea. 2011. MAPP: A scalable multi-agent path planning algorithm with tractability and completeness guarantees. *Journal of Artificial Intelligence Research* 42 (2011), 55–90.
- [22] P. R. Wurman, R. D’Andrea, and M. Mountz. 2008. Coordinating hundreds of cooperative, autonomous vehicles in warehouses. *AI Magazine* 29, 1 (2008), 9.
- [23] J. Yu and S. M. LaValle. 2013. Planning optimal paths for multiple robots on graphs. In *ICRA*. 3612–3617.
- [24] J. Yu and S. M. LaValle. 2013. Structure and intractability of optimal multi-robot path planning on graphs. In *AAAI*. 1444–1449.