

# **BALANCED MULTI ROBOT TASK ALLOCATION**

Multi robot path planning is one of the fundamental problems in robotics. The rate of scientific and industrial development made way for the use of multi robot in many fields. The team mission is that, the robot must visit tasks with some objective. Multi robot task allocation (MRTA) problems concentrate on minimization of total distance travelled by the robots. Some of research considers the utilization factor for the allocation of task to the robot instead of distance. So far the Multi robot task allocation problem does not concentrate on the priority of the task. Since in lot of real life application such as robotic search and rescue missions, environmental or hazardous clean-up missions where the task are arrive at the definite location with some priority (High, Medium, Low). The previous work on MRTA is not well suitable for this above application. the objective of the proposed work is to have minimum possible waiting time for high prioritized tasks next minimum to medium and low respectively.