

In this thesis, we explore the world of Multiagent pickup and delivery algorithms. Basic definitions, as well as simple extensions, are introduced to the reader. State-of-the-art algorithms are thoroughly described, analyzed, and tested in various environments based on multiple conditions. We describe the scalability of the algorithms and demonstrate it in multiple scenarios. The thesis includes a short overview of explainable plans, their motivation, and their implementation. Support software was created for conducting experiments, visualization, and making explainable plans.