Dear Reviewer,

Thank you for your useful advice. I have corrected some spelling mistakes and I have also completed Section 4.5 with one-way traversal constraints:

"The adjacency matrix of the cells can be created after dividing the map. This matrix is a $n \times 4$ matrix, where n is the number of cells. Rows of the matrix store the indices of the adjacent cells of every cell, in each direction. If two cells have common boundaries, and the vehicle can pass from one cell to the other, these cells are adjacent. Cells neighboring obstacles and cells in the edges of the map do not have 4 neighboring cells, in this case the neighboring obstacles and edges are considered as their neighbors. (An implementational solution can be if these false neighbors are stored with dummy indices e.g. -1). In case of one-way road sections, it is permitted to go from one cell to the other, but it is prohibited in the opposite direction, so the i^{th}cell is adjacent to the j^{th} cell, but it is not true vice versa. This means, that the i^{th} row of the adjacency matrix contains the j cell index in the appropriate column, but the j^{th}row contains a dummy index instead of the i index."

Thank you again for your helpful advice.