What is claimed is:

1. A task processing method for a plurality of robots, which is performed by a task processing device, wherein the task processing device and the plurality of robots are both deployed with a first communication module configured to perform bidirectional communication between the plurality of robots and the task processing device, the plurality of robots further comprise a second communication module configured to perform bidirectional communication between the plurality of robots, and the task processing method comprises:

identifying at least one robot of the plurality of robots as a disconnected robot in case that a heartbeat connection between the at least one robot and the task processing device is detected to be lost;

obtaining a historical position of the disconnected robot and a current position of a connected robot of the plurality of robots, wherein the connected robot is a robot that maintains a heartbeat connection with the task processing device;

for the disconnected robot, determining a target sending robot corresponding to the disconnected robot from the plurality of robots according to the historical position of the disconnected robot and a current position of the connected robot, wherein the target sending robot comprises the connected robot; and

sending task information of a current task of the disconnected robot to the disconnected robot through the target sending robot.

2. The task processing method according to claim 1, wherein

the determining the target sending robot corresponding to the disconnected robot from the plurality of robots comprises:

obtaining a historical position of another disconnected robot than the disconnected robot in case that each of distances between current positions of connected robots and a historical position of the disconnected robot is greater than a distance threshold;

determining the another disconnected robot, of which a historical position is at a distance from the historical position of the disconnected robot less than or equal to the distance threshold as a candidate disconnected robot according to the historical position of the another disconnected robot;

determining the connected robot of which a current position is at a distance from a historical position of the candidate disconnected robot less than or equal to the distance threshold as a candidate connected robot according to the historical position of the candidate disconnected robot and the current position of the connected robot; and

determining a target disconnected robot and a target connected robot corresponding to the disconnected robot from the candidate disconnected robot and the candidate connected robot as the target sending robot respectively.

3. The task processing method according to claim 2, wherein the sending the task information of the current task of the disconnected robot to the disconnected robot through the target sending robot comprises:

sending the task information of the current task of the disconnected robot to the disconnected robot through the target connected robot and the target disconnected robot sequentially.

4. The task processing method according to claim 2 or 3, further comprising:

sending task information of a current task of the target disconnected robot to the target disconnected robot through the target connected robot.

5. The task processing method according to claim 1, further comprising:

determining a target receiving robot corresponding to the disconnected robot from the plurality of robots, wherein the target receiving robot is configured to receive a result of performing a current task sent from the disconnected robot through the second communication module; and

receiving the result of performing the current task through the target receiving robot, wherein the target receiving robot comprises the connected robot.

6. The task processing method according to claim 5, wherein the receiving the result of performing the current task by the target receiving robot comprises:

receiving the result of performing the current task sent from the target receiving robot in case that the target receiving robot only comprises the connected robot; and

receiving the result of performing the current task through the disconnected robot of the target receiving robot and the connected robot of the target receiving robot sequentially in case that the target receiving robot comprises the disconnected robot and the connected robot.

7. The task processing method according to claim 5, wherein the target receiving robot and the target sending robot are completely same, partially same or completely different.

8. The task processing method according to claim 1, wherein the determining the target sending robot corresponding to the disconnected robot from the plurality of robots comprises:

determining the target sending robot corresponding to the disconnected robot from at least one connected robot in case that the distance between a current position of the at least one connected robot and the historical position of the disconnected robot is less than or equal to the distance threshold.

9. The task processing method according to claim 8, wherein the determining the target sending robot corresponding to the disconnected robot from the at least one connected robot comprises:

determining the connected robot of which a current position is at the shortest distance from the historical position of the disconnected robot from the at least one connected robot as the target sending robot corresponding to the disconnected robot.

10. The task processing method according to claim 1, wherein a difference between a wireless propagation distance of the second communication module and a wireless propagation distance of the first communication module is greater than a difference threshold under a same power consumption, where the difference and the difference threshold are positive integers.

11. The task processing method according to claim 10, wherein a current task is a follow task, and the second communication module is further configured to exchange real-time motion parameters, positions and road condition information between the plurality of robots performing the follow task.

12. The task processing method according to claim 11, wherein the motion parameters comprise at least one of a velocity, an

acceleration or a direction.

13. The task processing method according to any of claims 1 to 12, wherein the first communication module is a WIFI module, and the second communication module is a long-range radio LORA module.

14. A task processing method for a plurality of robots comprising a first communication module and a second communication module, wherein the first communication module is configured to perform bidirectional communication between the plurality of robots and a first communication module of a task processing device, and the second communication module is configured to perform bidirectional communication between the plurality of robots, the task processing method is performed by a robot of the plurality of robot, and the task processing method comprises:

receiving task information of a current task of a disconnected robot sent from the task processing device through the first communication module, and sending the task information of the current task of the disconnected robot to the disconnected robot through the second communication module in case that a heartbeat connection between the robot and the task processing device is not lost and the robot is determined as a target sending robot corresponding to the disconnected robot, wherein the disconnected robot is a robot whose heartbeat connection with the task processing device is lost;

receiving task information of a current task of the robot sent from the target sending robot corresponding to the robot through the second communication module in case that a heartbeat connection between the robot and the task processing device is lost, wherein the target sending robot comprises a connected

robot; and

in case that a heartbeat connection between the robot and the task processing device is lost and the robot is determined as a target sending robot corresponding to another disconnected robot, receiving task information of a current task of the another disconnected robot sent from another target sending robot through the second communication module, and sending the task information of the current task of the another disconnected robot to the another disconnected robot wherein the another target sending robot comprises the connected robot.

15. The task processing method according to claim 14, wherein the target sending robot comprises at least one robot at a distance from a corresponding disconnected robot less than or equal to a distance threshold, and in case that there are a plurality of target sending robots, series paths constituted by the plurality of target sending robots comprise a series path, in which the distance between any two adjacent target sending robots is less than or equal to the distance threshold.

16. A robot comprising:

a first communication module configured to perform bidirectional communication with a first communication module of a task processing device;

a second communication module configured to perform bidirectional communication with a second communication module of other robots; wherein:

task information of a current task of a disconnected robot sent from the task processing device is received through the first communication module, and the task information of the current task of the disconnected robot is sent to the disconnected robot through the second communication module in case that a heartbeat connection between the robot and the task

processing device is not lost and the robot is determined as a target sending robot corresponding to the disconnected robot, wherein the disconnected robot is a robot whose heartbeat connection with the task processing device is lost;

task information of a current task of the robot sent from a target sending robot corresponding to the robot is received through the second communication module, wherein the target sending robot comprises a connected robot in case that a heartbeat connection between the robot and the task processing device is lost; and

in case that a heartbeat connection between the robot and the task processing device is lost and the robot is determined as a target sending robot corresponding to another disconnected robot, task information of a current task of the another disconnected robot sent from another target sending robot is received through the second communication module, and the task information of the current task of the another disconnected robot is sent to the another disconnected robot, wherein the another target sending robot comprises the connected robot.

17. The robot according to claim 16, wherein the target sending robot comprises at least one robot at a distance from a corresponding disconnected robot less than or equal to a distance threshold, and in case that there are a plurality of target sending robots, series paths constituted by the plurality of target sending robots comprise a series path, in which the distance between any two adjacent target sending robots is less than or equal to the distance threshold.

18. An electronic device, comprising:

a memory; and

a processor coupled to the memory, wherein the processor is configured to perform the task processing method according to any of claims 1 to 15 based on instructions stored in the memory.

19. A computer-readable medium having computer program instructions stored thereon that, when executed by a processor, implement the task processing method according to any of claims 1 to 15.