

S10:at least one robot is identified as a disconnected robot



S20:a historical position of the disconnected robot and a current position of the connected robot among the plurality of robots are obtained



S 3 0 : for disconnected robot, a target sending robot corresponding to the disconnected robot is determined from the plurality of robots according to the historical position of the disconnected robot and a current position of the connected robot



S40:task information of a current task of disconnected robot is sent to the disconnected robot by the target sending robot

Fig. 1

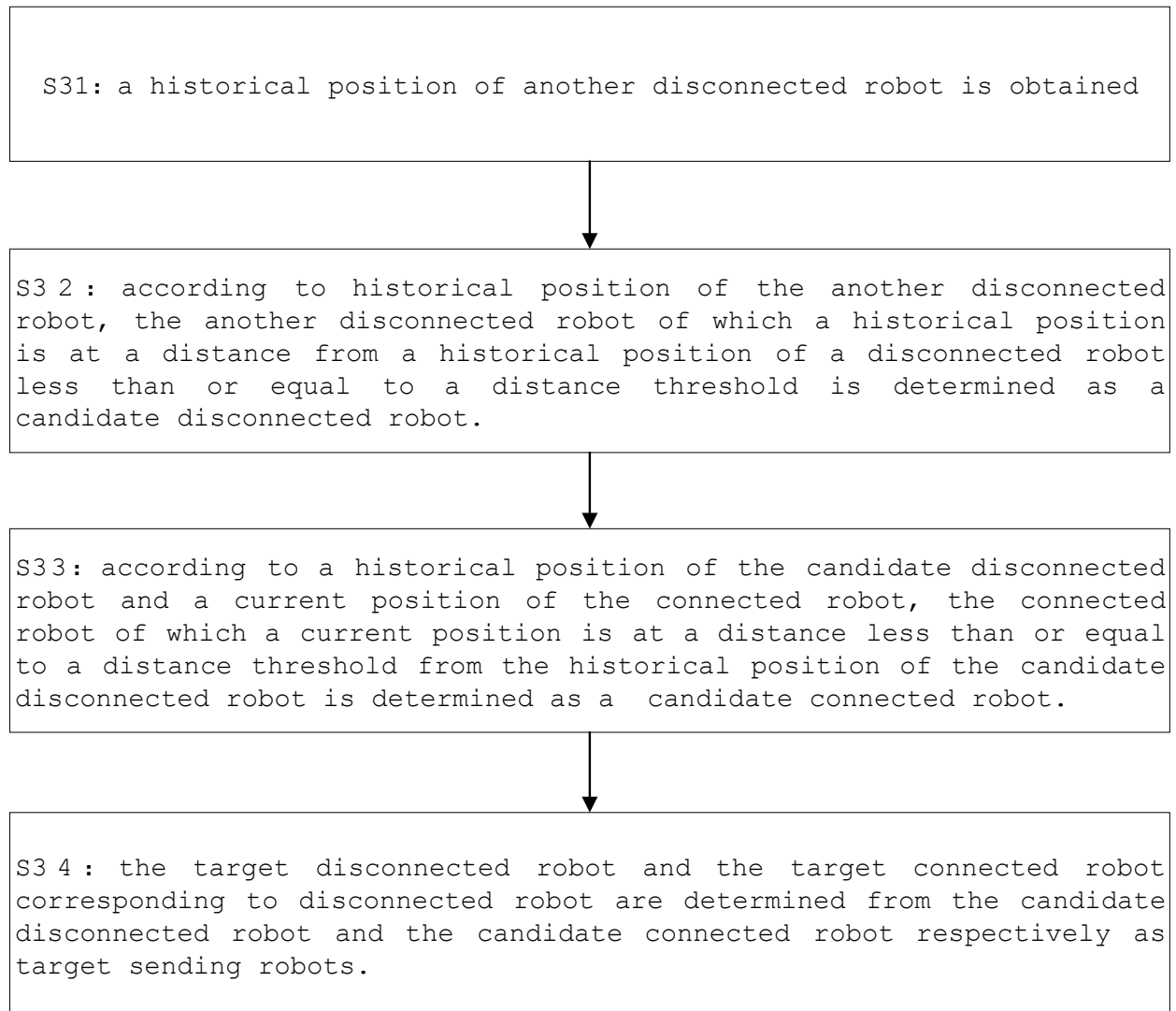


Fig. 2

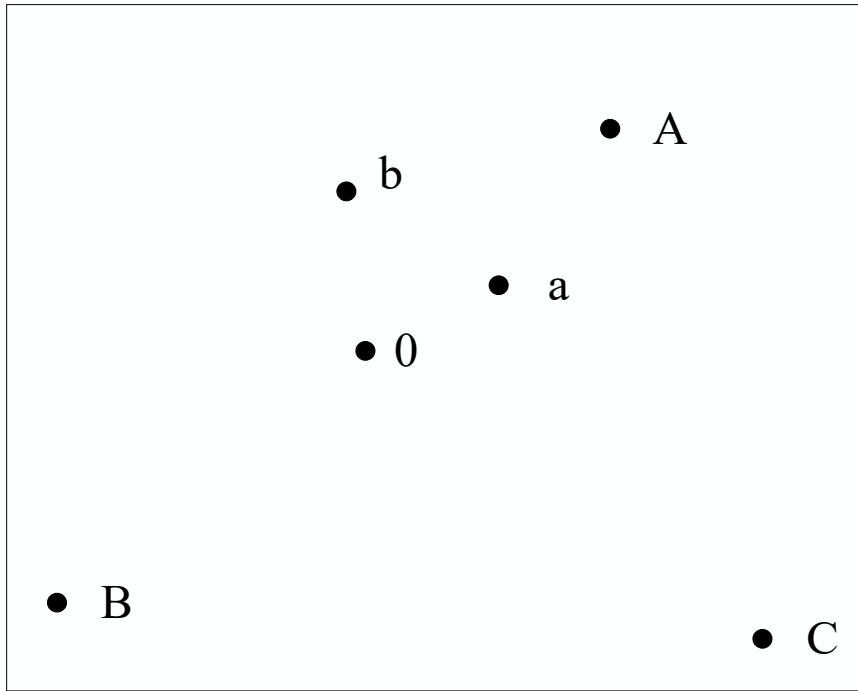


Fig. 3

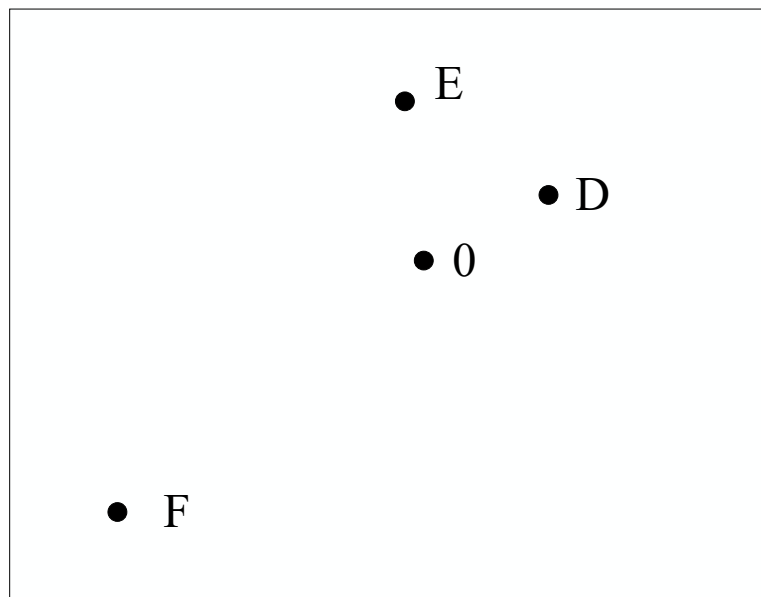


Fig. 4

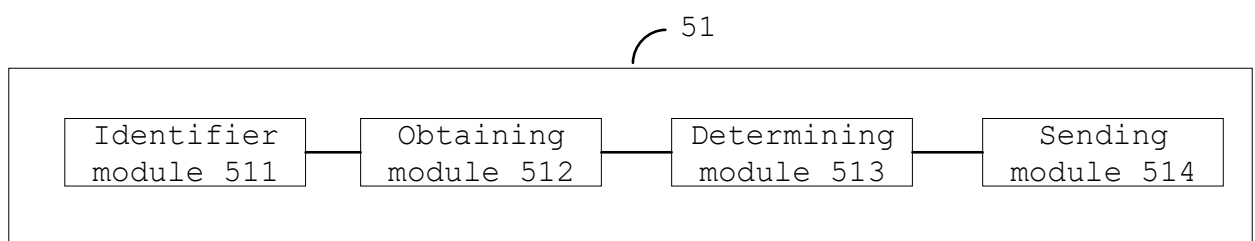


Fig. 5

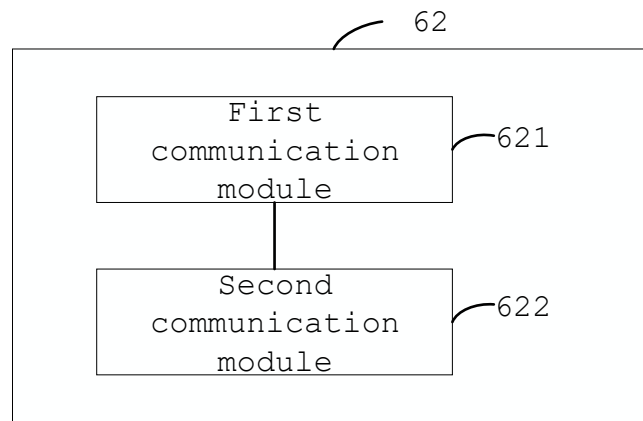


Fig. 6

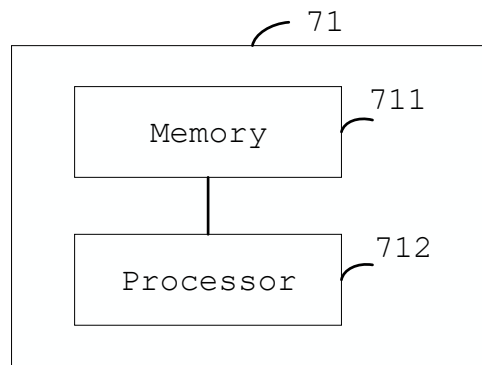


Fig. 7

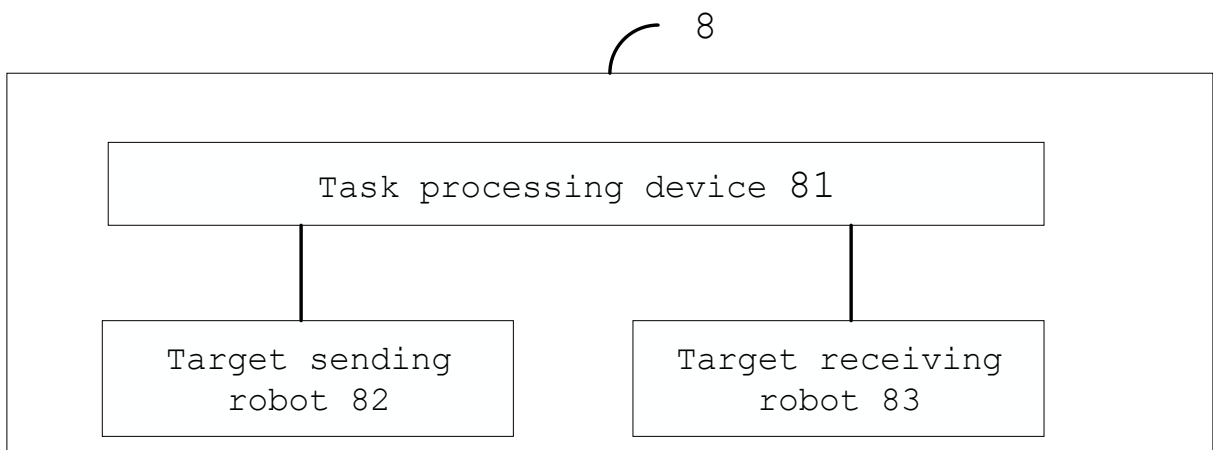


Fig. 8

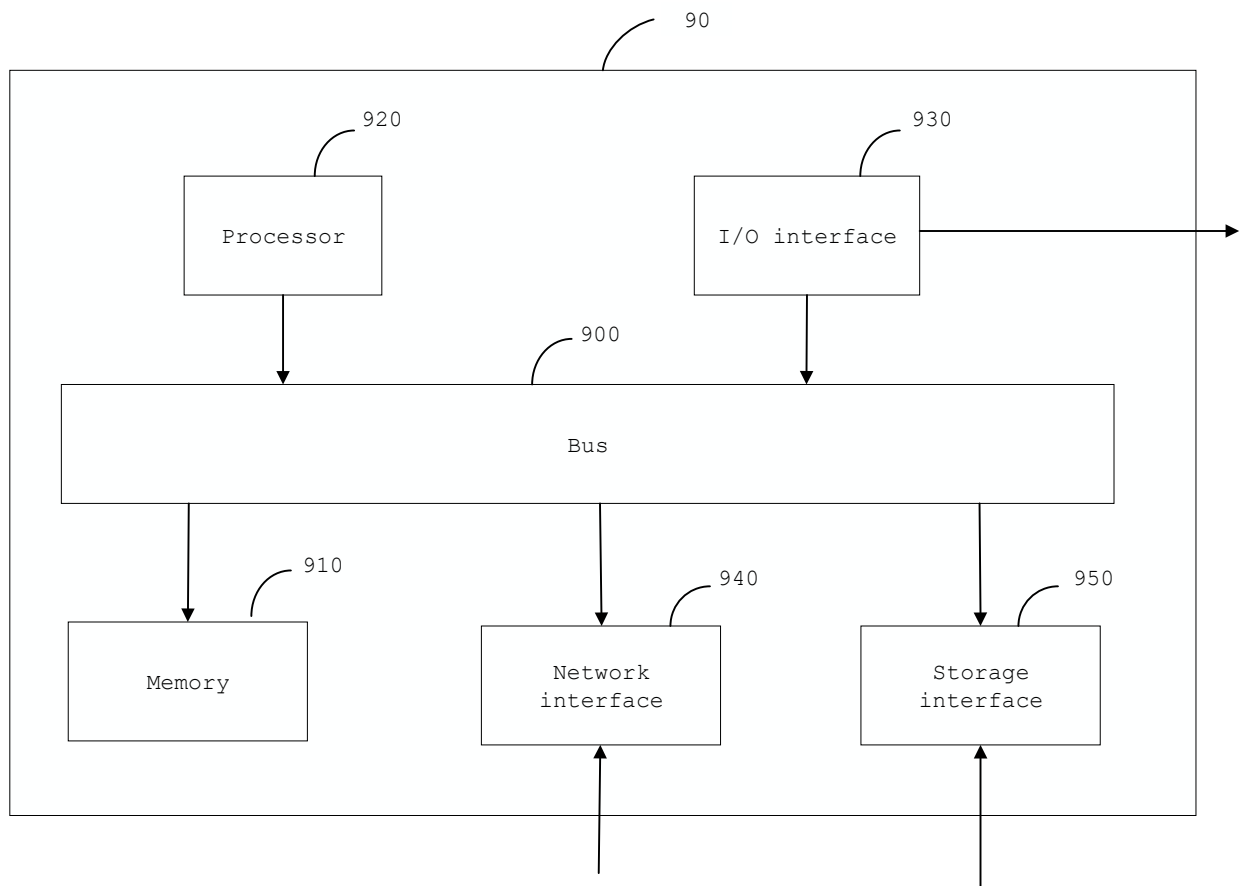


Fig. 9