

## **ABSTRACT**

The present disclosure relates to a task processing method, apparatus and system for multiple robots, and a robot. A first communication module is deployed in the task processing apparatus and multiple robots, and the first communication modules are used for bidirectional communication between the robots and the task processing apparatus. The multiple robots also each comprise a second communication module, which is used for bidirectional communication between the robots. The task processing method comprises: when detected that a heartbeat connection between at least one robot and a task processing apparatus is disconnected, tagging the at least one robot as a lost robot; obtaining historical positions of the lost robots and a current position of a non-lost robot; according to the historical positions of the lost robots and the current position of the non-lost robot, determining a target sending robot corresponding to each lost robot, wherein the target sending robot comprises a non-lost robot; and sending task information of a current task of each lost robot to each lost robot by means of the target sending robot.