

FT-MSTC*: An Efficient Fault Tolerance Algorithm for Multi-robot Coverage Path Planning

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- Present a new efficient fault tolerance algorithm for multi-robot coverage path planning using optimization method.
- After failures, FT-MSTC* will minimize the overall maximum coverage cost while considering both the accomplished tasks and the remaining tasks.
- Our experiments show FT-MSTC* outperformed other coverage path planning algorithms in terms of the overall maximum coverage cost.

