1. Algorithm → pseudo

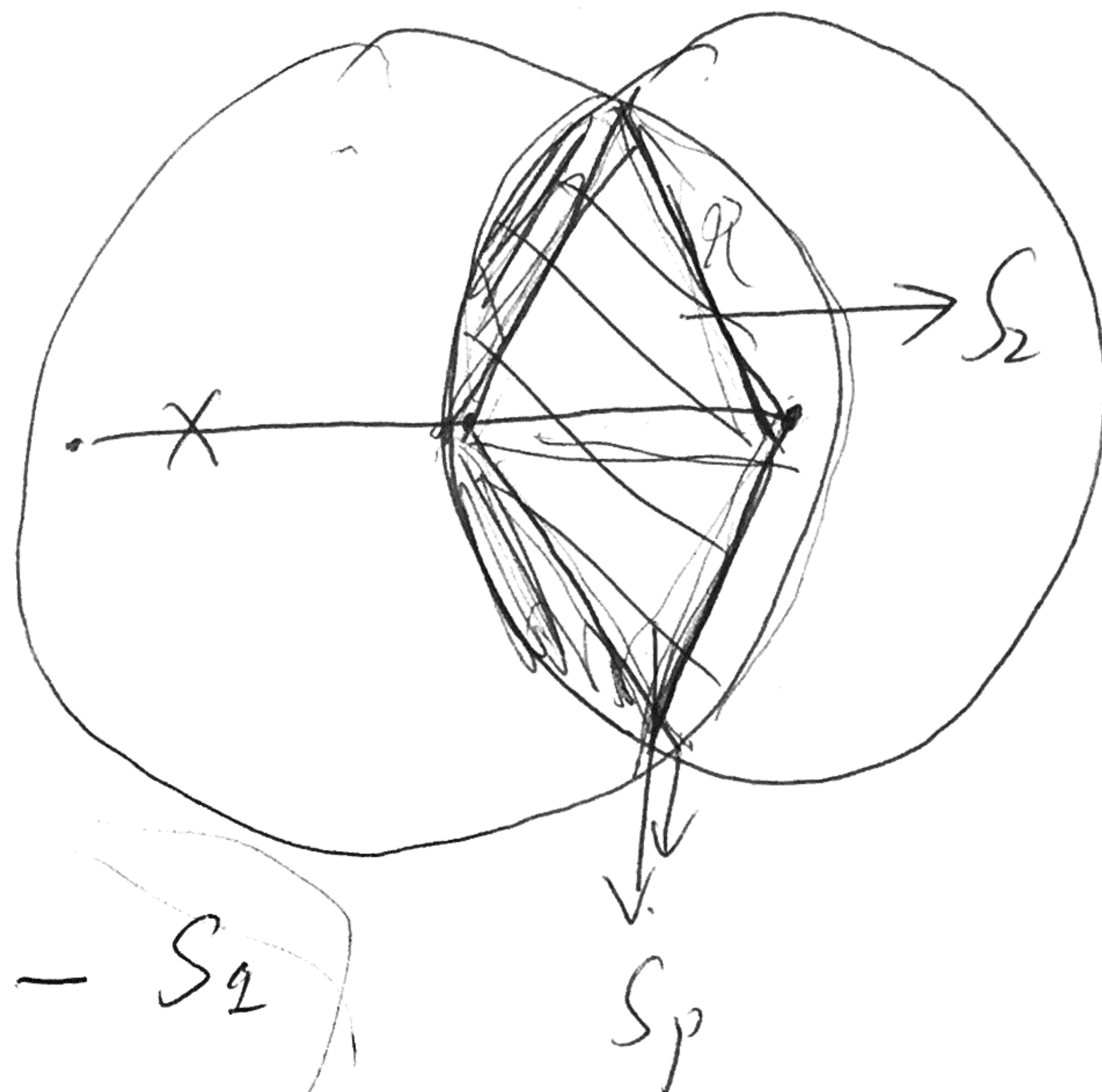2. picture → report   romba → search →

    irobot

3. |∑ communication range|
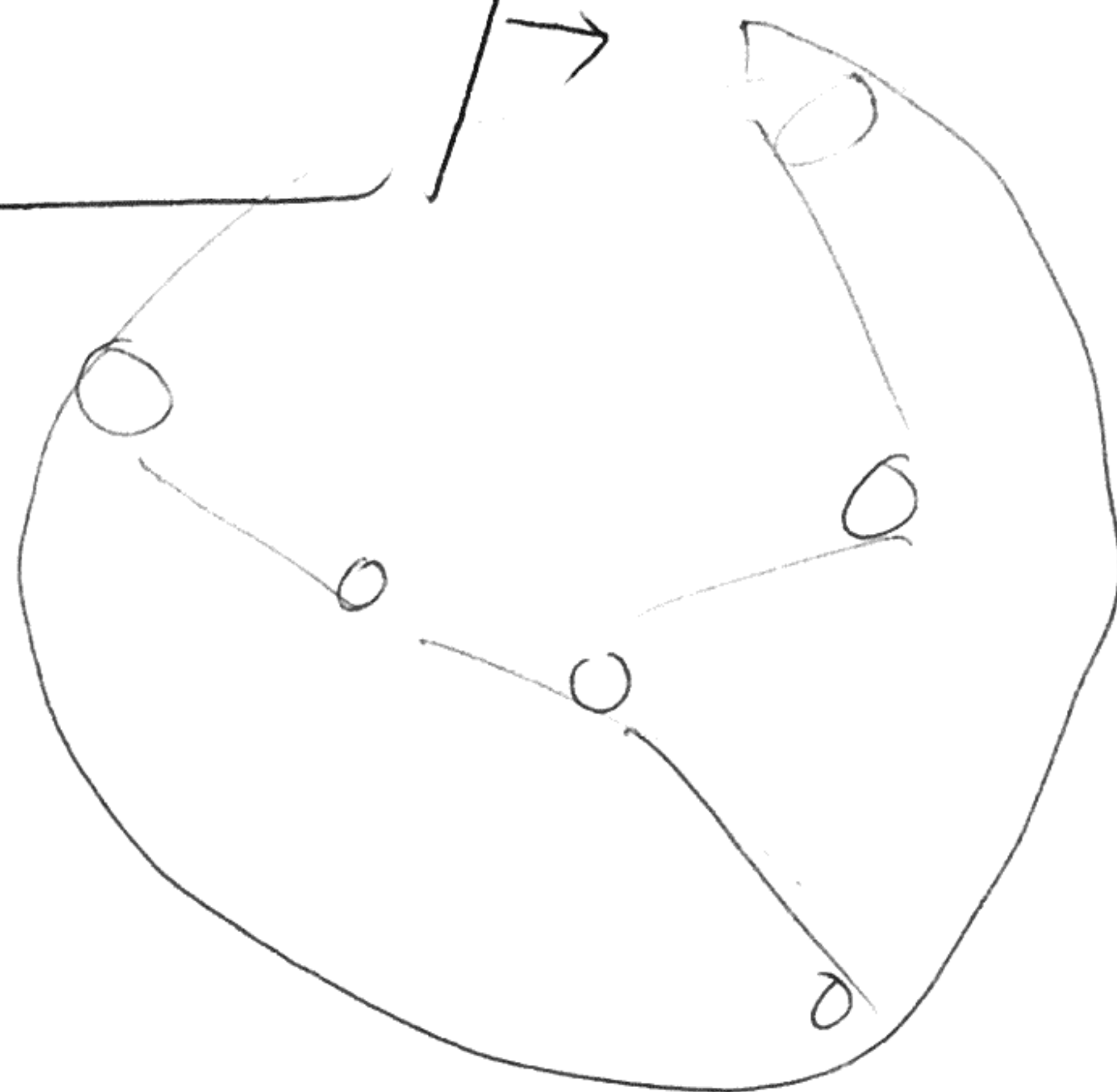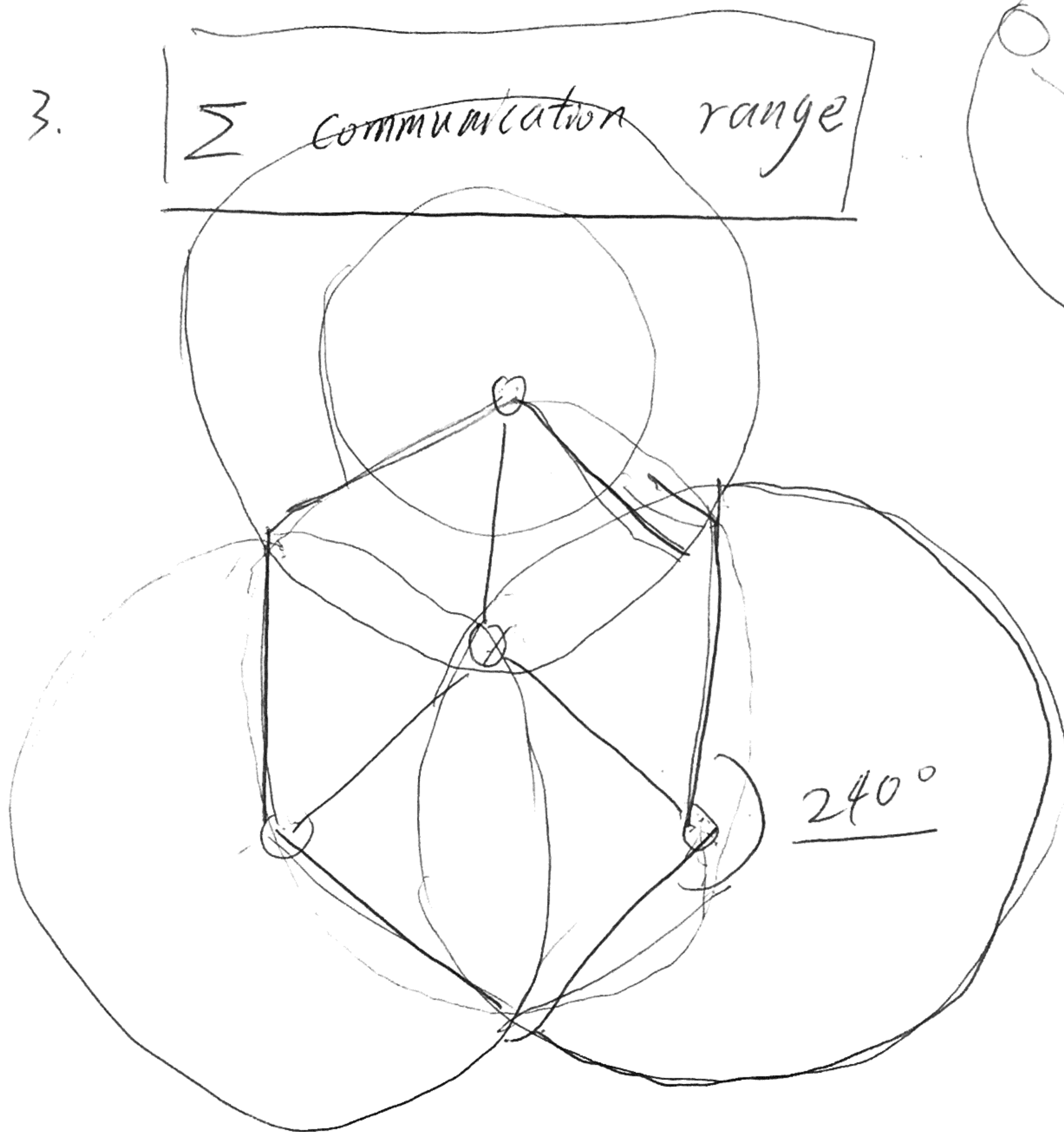
240°

△
□

= area_poly + 3 * area_sector
final position for each robot (2 sets of data)

minimal coverage sensors

case 1:

2 robots

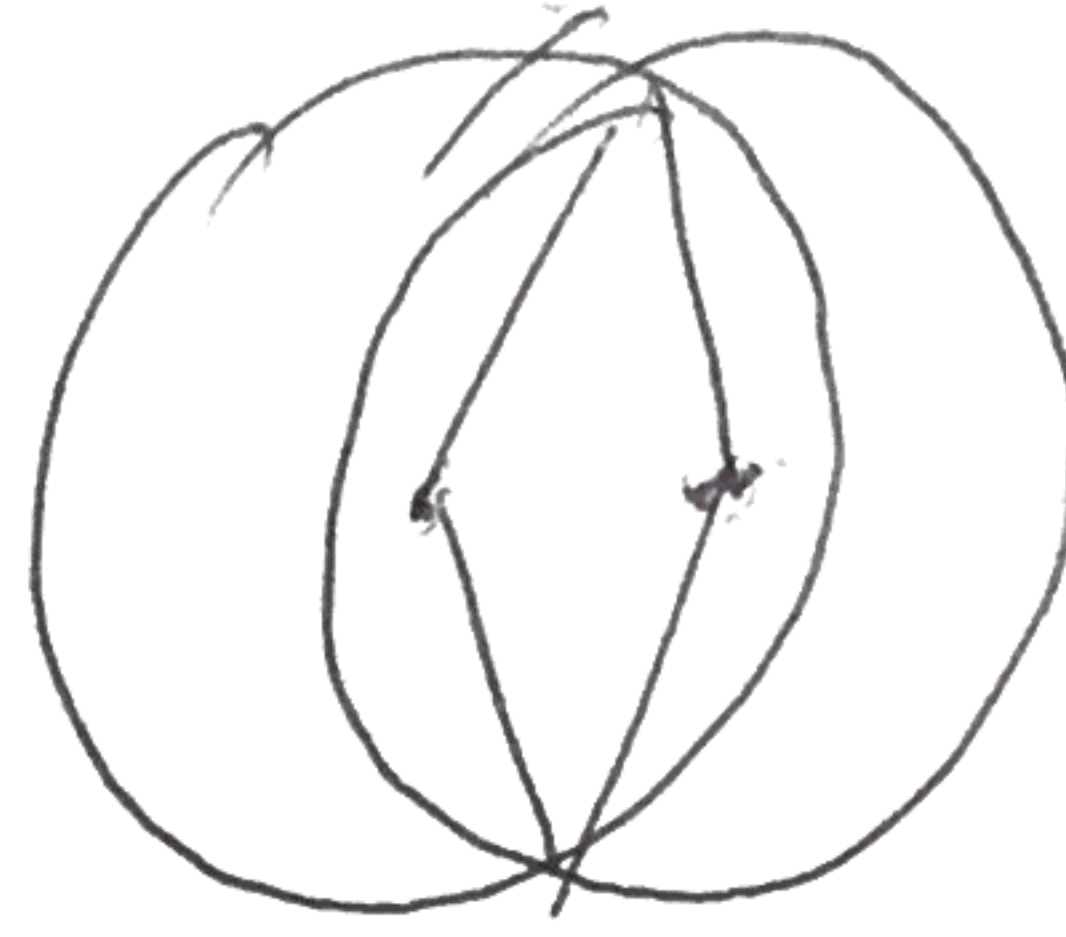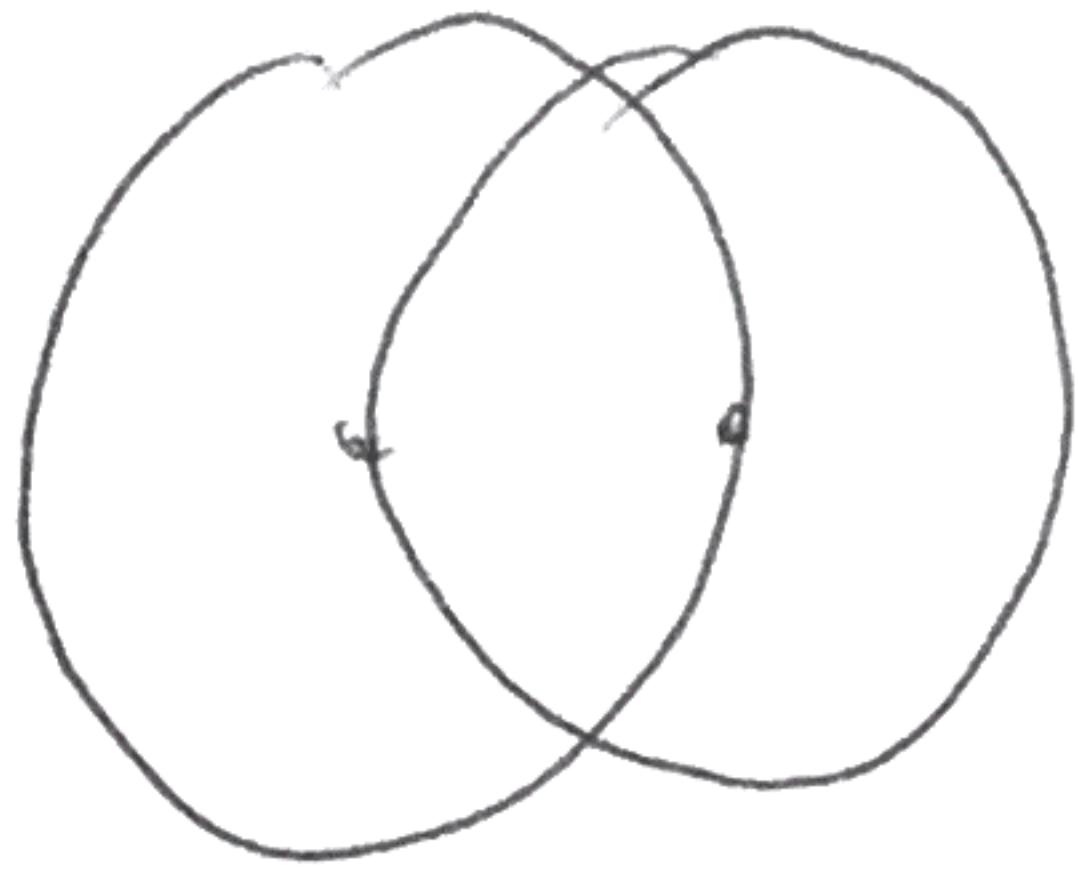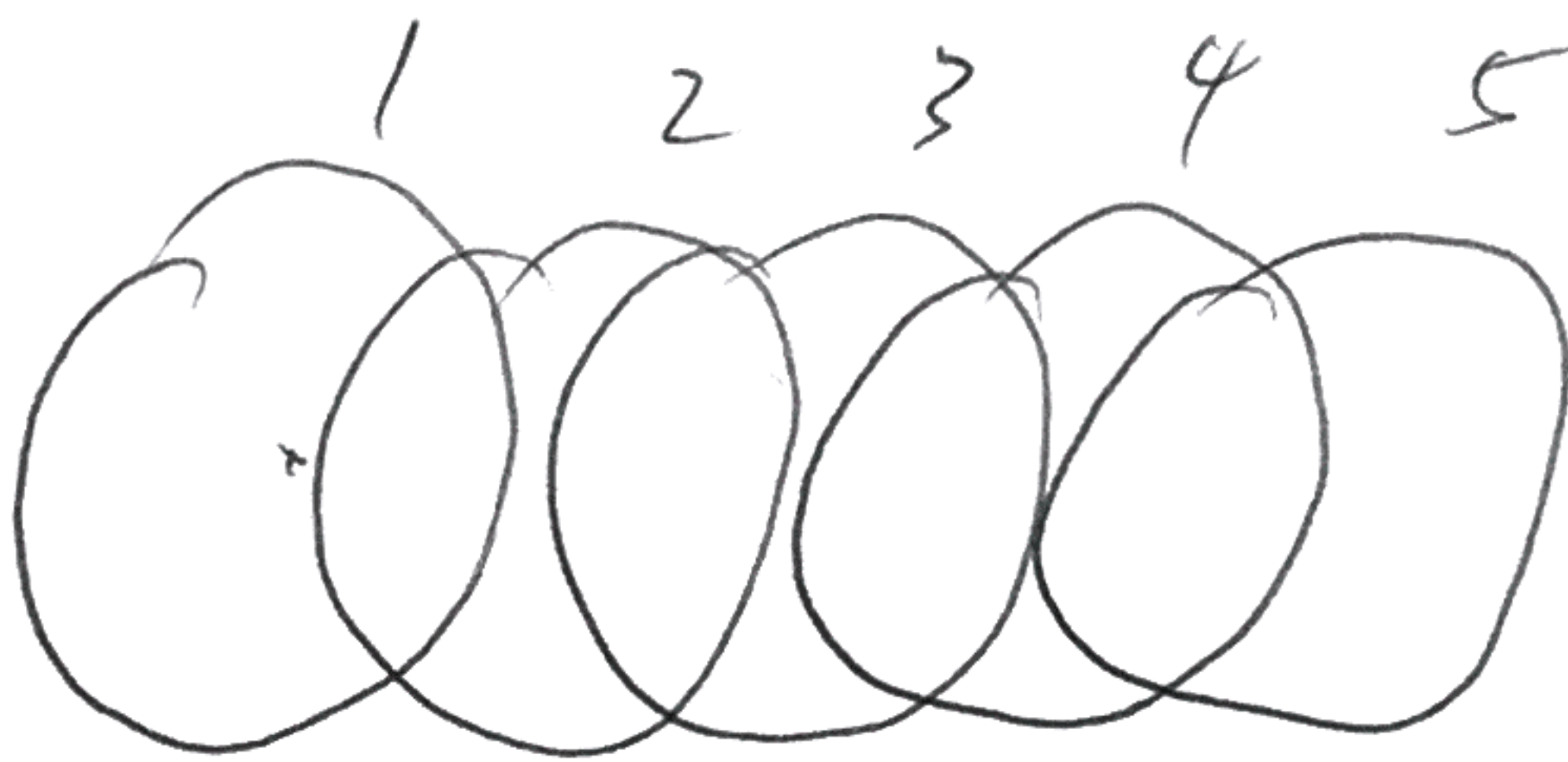$$\underline{2 \pi R^2 - S_2}$$

$$S_2 = (2 S_2 - S_p)$$

overlaped   sector   area of poly

case 2:   use approximation

actual coverage

1 2 3 4 5

$$S * \pi R^2 - \boxed{4 S_1}$$

4.