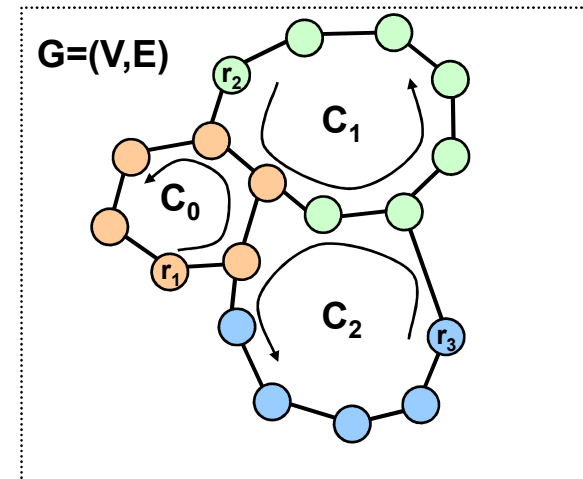


# A Novel Approach to Path Planning for Multiple Robots in Bi-connected Graphs

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- A **group of robots** is trying to move to given goal positions in an environment
- The environment is modeled as an **undirected graph** where robots are in the vertices
- A novel polynomial-time solution algorithm for environments with **bi-connected graphs**
- Experimental evaluation showed that the new algorithm is **practically more efficient** than comparable techniques



Robots moving in  
a bi-connected graph