

WHAT IS CLAIMED IS:

1. A method for robot elevator-taking path planning, comprising:
step S1, obtaining a starting floor and an ending floor of the robot;
5 step S2, determining all elevator groups that can reach the starting floor
to form a cache path sequence; wherein, each cache path in the cache path
sequence includes an elevator group sequence, an elevator sequence, a floor
sequence and an expected time point sequence;
step S3, traversing all the cache paths, if the elevator group
10 corresponding to the traversed cache path can reach the ending floor directly,
adding the cache path to an available path sequence; otherwise, taking a last
floor in the floor sequence of the elevator group corresponding to a current
cache path as a current floor;
traversing all transfer elevator groups reachable from the current floor,
15 and excluding duplicate elevator groups in all transfer elevator groups and
the current cache path; if the traversed transfer elevator group can reach the
ending floor, adding the transfer elevator group and the ending floor to the
current cache path, and adding the current cache path to the available path
sequence as an elevator-taking path; and
20 step S4, repeating the step S3 until all cache paths are traversed.
2. A computer device, comprising a memory and one or more processors,
wherein computer-readable instructions are stored in the memory, and the
computer-readable instructions, when being executed by the one or more
processors, enable the one or more processors to execute the steps of the
25 method according to claim 1.
3. A computer-readable storage medium storing a computer program,
wherein the computer program, when executed by a processor, implements
the steps of the method according to claim 1.