Claims

1. Method for a control, by a supervising server, of a movement of a fleet of autonomously guided vehicles in a movement area equipped with a plurality of wireless Wi-Fi access points each comprising at least one geolocation means and a Wi-Fi communication module, said method comprising a step of recording the coordinates of these access points and steps of changing access point, which are executed by each of the autonomously guided vehicles, said steps consisting of controlling the disconnection of the Wi-Fi communication module from an active access point and reconnection to a $SSID_i$ access point for which the coordinates recorded in a database are the closest of the coordinates determined by the geolocation means,

characterized in that said geolocation means for the autonomously guided vehicles consist of means of measuring the relative movement of the vehicle in relation to a plurality of physical reference elements in the movement area, and in that said reconnection step also consists of controlling the reconnection to a nearest second $SSID_{i+1}$ access point

- if an authentication delay of said communication module with the $SSID_i$ access point exceeds a predetermined period T_{aut}

- and/or if a response period of said server to a ping transmitted by said communication module with the $SSID_i$ access point exceeds a predetermined period T_{ping}

the method consisting of controlling a safety stopping of said vehicle if the reconnection delay exceeds a period T_{safety}.

2. Method for the control, by a supervising server, of the movement of a fleet of autonomously guided vehicles according to claim 1, characterized in that said step of recording the coordinates of said access points consists of moving a map acquisition vehicle between a plurality of geolocation points in the work area and controlling, while

the vehicle is immobilized at an acquisition point, the recording of the geographic coordinates and the identifiers of the Wi-Fi access points detected, then controlling the movement to a new acquisition point, to form a digital geolocation map of the access points, said digital map being recorded in the local memory of each of said autonomously guided vehicles.

3. Method for the control, by a supervising server, of the movement of a fleet of autonomously guided vehicles according to claim 2, characterized in that said method also comprises a step of recording access points that are absent from said digital map and the coordinates thereof by at least some of the autonomously guided vehicles, and periodically transferring said data to the supervising server.

4. Method for the control, by a supervising server, of the movement of a fleet of autonomously guided vehicles according to claim 1, characterized in that the movement of the autonomously guided vehicle is controlled according to data received from the supervising server, which data are buffered during the roaming sequences.

5. Method for the control, by a supervising server, of the movement of a fleet of autonomously guided vehicles according to claim 1, characterized in that the processor of the autonomously guided vehicle controls the safety stopping of the movement if the predetermined roaming delay is exceeded.