Claims

[Claim 1]

A control method of a moving body that automatically moves, the control method comprising:

a step of moving the moving body along a reference path;

a step of causing a sensor provided on the moving body to detect an obstacle located on a side toward a first direction that is a traveling direction of the moving body when the moving body is moving along the reference path;

a step of stopping the moving body in a case where the obstacle is present on the side toward the first direction;

a step of setting a reverse path that returns to a second direction opposite to the first direction based on the reference path; and

a step of moving the stopped moving body to a position closer to a position of the moving body when the obstacle is detected, along the reverse path.

[Claim 2]

The control method according to claim 1,

wherein, in the step of setting the reverse path, a path that extends toward the second direction along the reference path is set as the reverse path.

[Claim 3]

The control method according to claim 1,

wherein, in the step of setting the reverse path, a path that extends toward the second direction along a movement trajectory on which the moving body has actually

moved along the reference path is set as the reverse path.

[Claim 4]

The control method according to any one of claims 1 to 3,

wherein, in a case where a position of the moving body when the obstacle is detected and a position of the obstacle satisfy a predetermined relationship, the moving body is stopped and then moved along the reverse path.

[Claim 5]

The control method according to any one of claims 1 to 3,

wherein, in the step of moving the moving body along the reverse path, the moving body is moved to a predetermined reverse position, and

the control method further comprises:

a step of setting an avoidance path that extends from the reverse position toward the first direction while avoiding the obstacle based on a position of the obstacle; and

a step of moving the moving body that has moved to the reverse position, along the avoidance path.

[Claim 6]

The control method according to claim 5,

wherein, in the step of setting the reverse path, a position corresponding to a detection position that is a position of the moving body when the obstacle is detected, a position between the detection position and the position of the obstacle, or a position farther from the obstacle than the detection position is set as the reverse position.

[Claim 7]

The control method according to claim 5, further comprising:

a step of setting, in a case where a second moving body different from a first moving body that has moved along the avoidance path passes through a predetermined distance range from the obstacle, an avoidance path for the second moving body based on the avoidance path for the first moving body; and

a step of moving the second moving body along the avoidance path without stopping the second moving body and reversing the second moving body.

[Claim 8]

A computer-readable recording medium having stored thereon a program for causing a computer to execute a control method of a moving body that automatically moves, the program causing the computer to execute:

a step of moving the moving body along a reference path;

a step of causing a sensor provided on the moving body to detect an obstacle located on a side toward a first direction that is a traveling direction of the moving body when the moving body is moving along the reference path;

a step of stopping the moving body in a case where the obstacle is present on the side toward the first direction;

a step of setting a reverse path that returns to a second direction opposite to the first direction based on the reference path; and

a step of moving the stopped moving body to a position closer to a position of the moving body when the obstacle is detected, along the reverse path.

[Claim 9]

A moving body that automatically moves, comprising:

a movement control unit that moves the moving body along a reference path;

a detection control unit that causes a sensor provided on the moving body to detect an obstacle located on a side toward a first direction that is a traveling direction of the moving body when the moving body is moving along the reference path; and

a reverse path acquisition unit that acquires a reverse path that returns to a second direction opposite to the first direction, the reverse path being set based on the reference path,

wherein the movement control unit

stops the moving body in a case where the obstacle is present on the side toward the first direction, and

moves the stopped moving body to a position closer to a position of the moving body when the obstacle is detected, along the reverse path.