

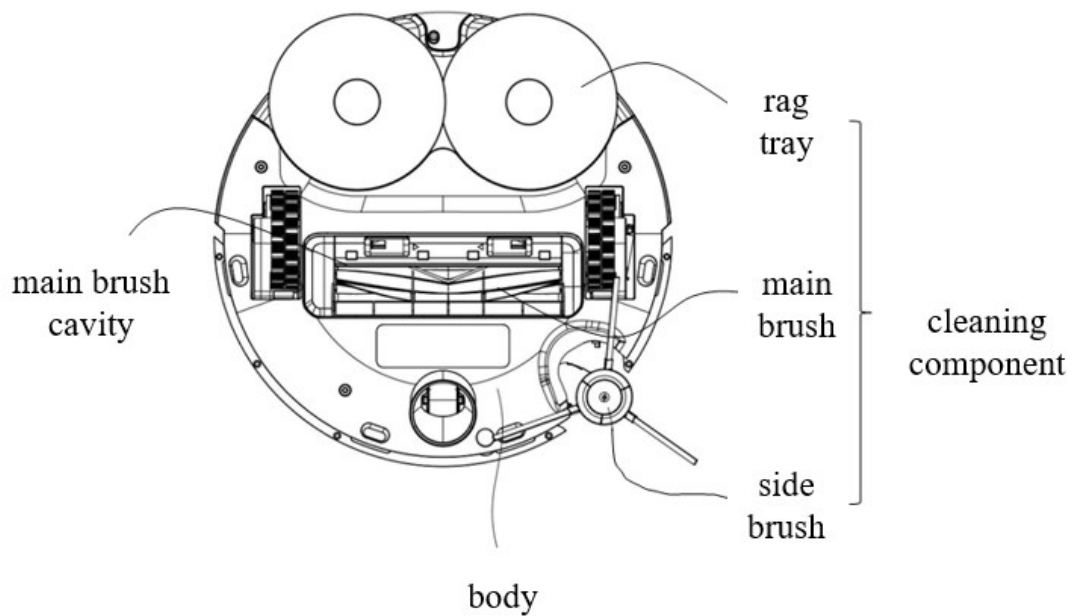


FIG. 1

During travel of the cleaning robot, when an obstacle moves within a detection range of the sensor system, when a distance between the obstacle and the cleaning robot along a central axis of the cleaning robot is less than a first preset detection threshold, when a maximum value among included angles between connection lines constituted by a first reference point of the cleaning robot and second reference points of the obstacle and a current traveling direction of the cleaning robot is greater than a third preset detection threshold, and when a minimum value among the included angles between the connection lines constituted by the first reference point of the cleaning robot and the second reference points of the obstacle and the current traveling direction of the cleaning robot is less than the third preset detection threshold, performing an action away from the obstacle to enable the sensor system to acquire three-dimensional information of the obstacle; where the central axis of the cleaning robot is parallel to the current traveling direction of the cleaning robot, the first reference point is one point closer to the obstacle along the current traveling direction in intersection points of a body boundary of the cleaning robot and the central axis of the cleaning robot, the second reference points are intersection points of an outer peripheral boundary of the obstacle and a reference line of the obstacle, and the reference line is perpendicular to the central axis

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FIG. 2

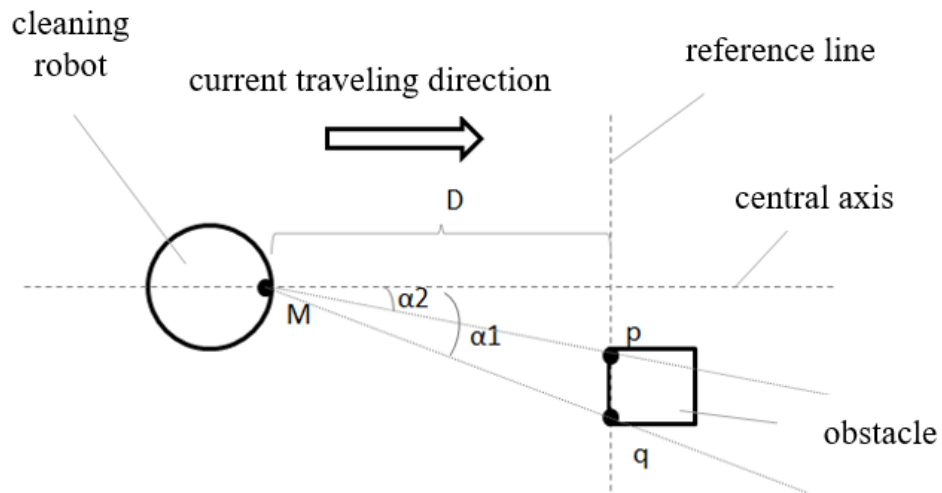


FIG. 3

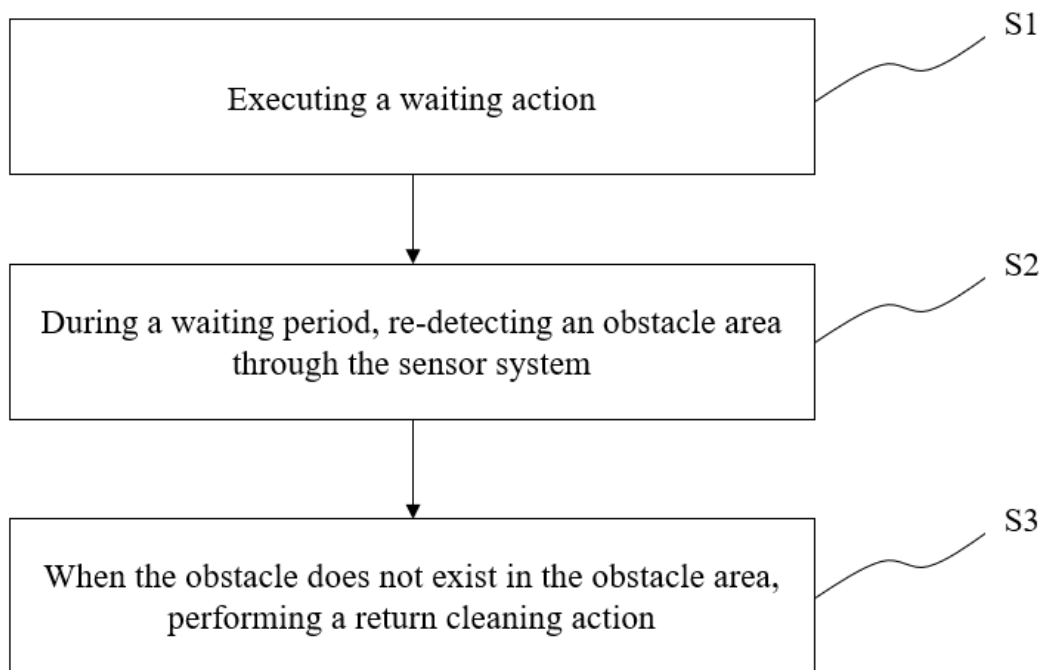


FIG. 4

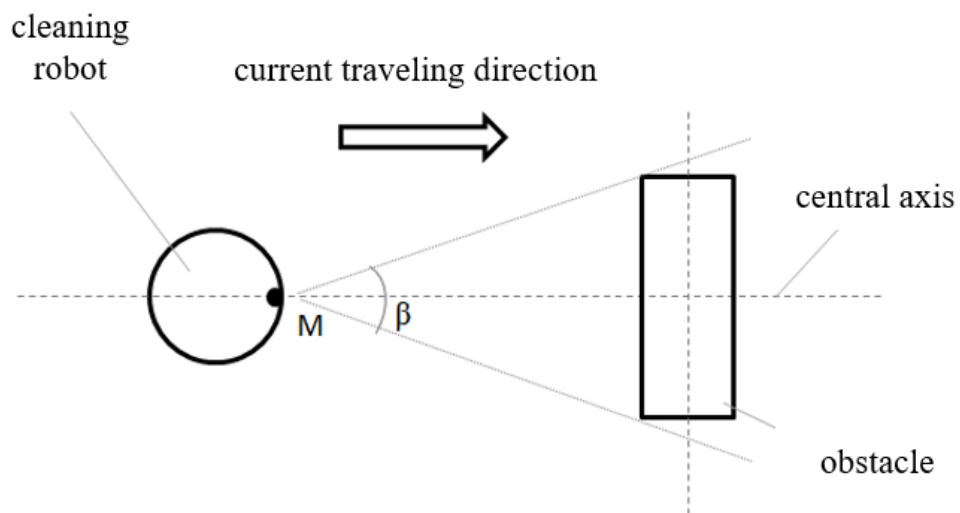


FIG. 5

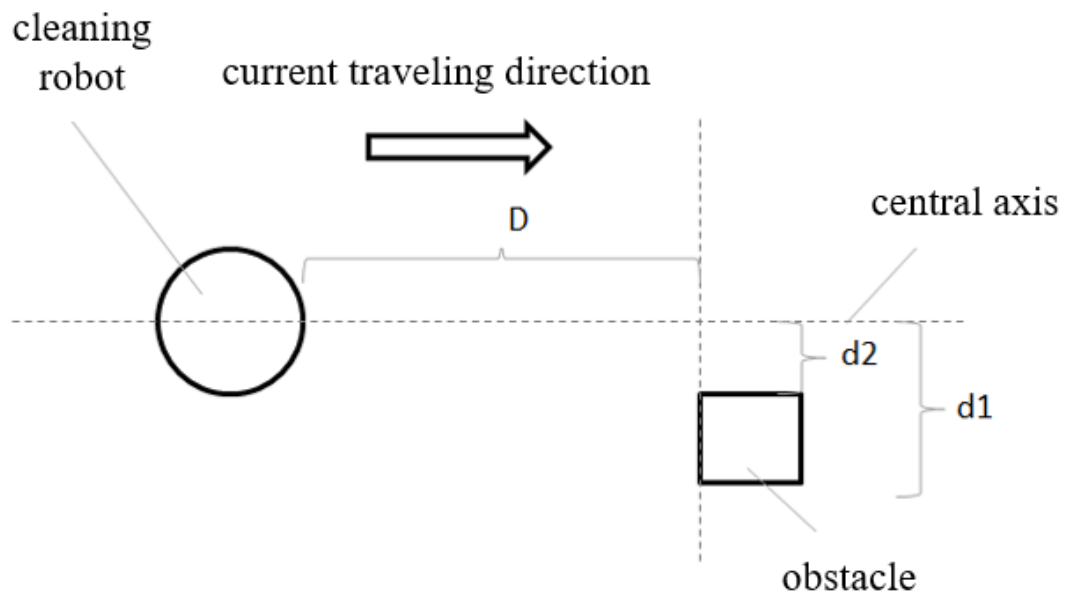


FIG. 6

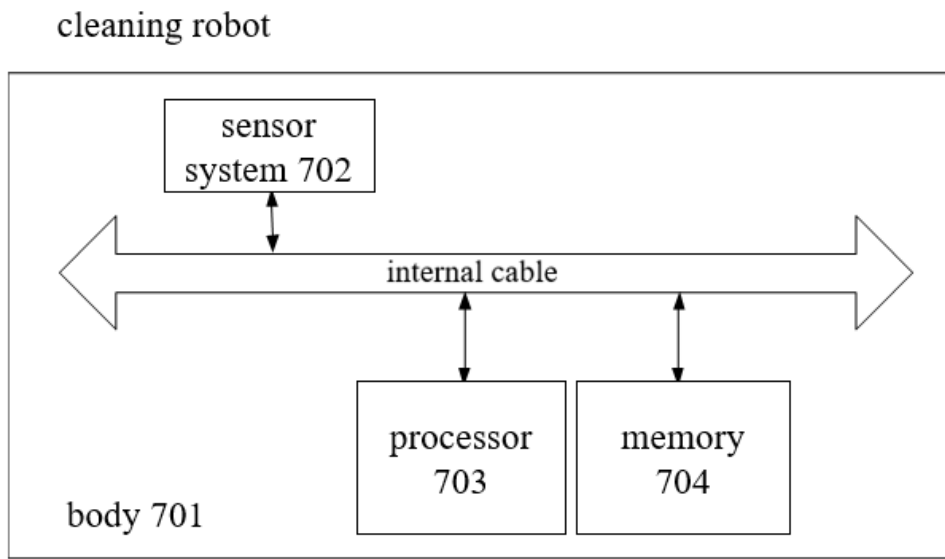


FIG. 7