

ABSTRACT

In order to grasp a relative positional relationship between a picking robot and a conveyance tool based on two-dimensional captured image data and enable control of a picking operation, the captured image data obtained by photographing the conveyance tool by a two-dimensional camera is acquired, a marker included in the captured image data is specified, a position and a photographing angle of the two-dimensional camera is specified based on how the marker appears, the relative positional relationship between the conveyance tool and the picking robot is specified, a predetermined identification symbol as the marker appearing on the captured image data is read to acquire control support information, a control content of an operation of the picking robot is determined using information regarding the relative positional relationship between the conveyance tool and the picking robot and the control support information, and control of the picking robot is performed based on the determined control content.