Claims

1. An electric scooter piloting method, comprising:

receiving a driving instruction; and

in response to the driving instruction, piloting the electric scooter to a target charging device according to a navigation path at least in the following manner: lowering a gravity center of the electric scooter.

2. The method as claimed in claim 1, wherein before piloting the electric scooter to the target charging device according to the navigation path at least in one of the following manners: lowering a gravity center of the electric scooter; and under a condition in which an obstacle is detected, controlling the electric scooter to avoid the obstacle or wait for predetermined time, the method further comprises:

detecting, via a detection component on the electric scooter, whether the obstacle is present or not within a predetermined range from the electric scooter.

3. The method as claimed in claim 1, wherein lowering the gravity center of the electric scooter comprises at least one of the followings:

controlling a support rod of the electric scooter to automatically fold to lower the gravity center of the electric scooter; and

controlling the support rod of the electric scooter to automatically reduce a height of the support rod to lower the gravity center of the electric scooter.

4. The method as claimed in claim 2, wherein the detection component at least comprises one of the followings: a camera, a radar assembly and a sensor.

5. The method as claimed in claim 1, wherein before piloting the electric scooter to the target charging device according to the navigation path at least in one of the following manners: lowering a gravity center of the electric scooter; and under a condition in which an obstacle is detected, controlling the electric scooter to avoid the obstacle or wait for predetermined time, the method further comprises:

use training wheels provided on the electric scooter to prevent the electric scooter from turning over.

6. The method as claimed in claim 1, wherein the navigation path comprises: a path from a current geographical position of the electric scooter to a target geographical position of the target charging device, wherein the current geographical position is acquired by a Global Position System (GPS) module of the electric scooter.

7. The method as claimed in claim 1, wherein the method further comprises:

in response to the driving instruction, piloting the electric scooter to a target charging device according to a navigation path in the following manner: under a condition in which an obstacle is detected, controlling the electric scooter to avoid the obstacle or wait for a predetermined period of time.

8. An electric scooter, comprising a memory and a processor, wherein the memory stores a computer program; and the computer program is configured to implement the following program modules when being executed by the processor:

a receiving module, configured to receive a driving instruction; and

a processing module, configured to pilot, in response to the driving instruction, the electric scooter to a target charging device according to a navigation path at least in the following manner: lowering a gravity center of the electric scooter.

9. The electric scooter as claimed in claim 8, wherein the electric scooter further comprises: a detection component; and the detection component is configured to detect whether the obstacle is present or not within a predetermined range from the electric scooter.

10. The electric scooter as claimed in claim 8, wherein the electric scooter further comprises: training wheel, provided on the electric scooter.

11. The electric scooter as claimed in any one of claims 8-10, wherein the electric scooter further comprises: a Global Position System (GPS) module, configured to acquire a current geographical position of the electric scooter.

12. The electric scooter as claimed in any one of claims 8-10, wherein the electric scooter further comprises:

a lowering module, configured to control a support rod of the electric scooter to automatically fold to lower the gravity center of the electric scooter; or control the support rod of the electric scooter to automatically reduce a height of the support rod to lower the gravity center of the electric scooter.

13. The electric scooter as claimed in claim 12, wherein the detection component at least comprises one of the followings: a camera, a radar assembly, and a sensor.

14. The electric scooter as claimed in claim 8, wherein the processing module is further configured to pilot, in response to the driving instruction, the electric scooter to a target charging device according to a navigation path in the following manner: under a condition in which an obstacle is detected, controlling the electric scooter to avoid the obstacle, or wait for a predetermined period of time.

15. A storage medium, wherein the storage medium stores a computer program, and the computer program is configured to execute an electric scooter piloting method, the method comprising: receiving a driving instruction; and in response to the driving instruction, piloting the electric scooter to a target charging device according to a navigation path at least in the following manner: lowering a gravity center of the electric scooter.

16. The storage medium as claimed in claim 15, wherein the computer program is configured to execute an electric scooter piloting method, the method comprising: detecting, via a detection component on the electric scooter, whether the obstacle is present or not within a predetermined range from the electric scooter.

17. The storage medium as claimed in claim 15, wherein the computer program is configured to execute an electric scooter piloting method, the method comprising: lowering the gravity center of the electric scooter comprises at least one of the followings:

controlling a support rod of the electric scooter to automatically fold to lower the gravity center of the electric scooter; and

controlling the support rod of the electric scooter to automatically reduce a height of the support rod to lower the gravity center of the electric scooter.

18. The storage medium as claimed in claim 15, wherein the computer program is configured to execute an electric scooter piloting method, the method comprising: use training wheels provided on the electric scooter to prevent the electric scooter from turning over.

19. The storage medium as claimed in claim 15, wherein the computer program is configured to pilot, in response to the driving instruction, the electric scooter to a target charging device according to a navigation path in the following manner: under a condition in which an obstacle is detected, controlling the electric scooter to avoid the obstacle, or wait for a predetermined period of time.