What is claimed is

1. A parcel dropping method for a parcel sorting system, comprising:

operating a conveying device to receive a parcel and move towards a delivery target; and

delivering, by the conveying device, the parcel to the delivery target after the conveying device moves to a delivery region, wherein a motion speed of the conveying device is not equal to zero when the conveying device delivers the parcel;

wherein the operating the conveying device to receive the parcel and move towards the delivery target comprises:

delivering, by the conveying device, the parcel to the delivery target at a determined delivery speed in a determined delivery distance, wherein the determined delivery distance and the determined delivery speed are calculated according to a size parameter of a to-be-delivered parcel and a size parameter of the delivery target.

2. The parcel dropping method of claim 1, further comprising:

before the delivering, by the conveying device, the parcel to the delivery target, determining whether the delivery region satisfies a condition for delivering the parcel when the conveying device is in motion; and

wherein the delivering, by the conveying device, the parcel to the delivery target after the conveying device moves to the delivery region comprises:

in condition that the condition is satisfied, delivering, by the conveying device, the parcel to the delivery target after the conveying device moves to the delivery region.

3. The parcel dropping method of claim 1, wherein the delivering, by the conveying device, the parcel to the delivery target after the conveying device moves to the delivery region comprises:

delivering, by the conveying device, the parcel to the delivery target during a uniform motion.

4. The parcel dropping method of claim 1, wherein the conveying device moves in a first direction in parallel with the delivery target.

5. The parcel dropping method of claim 4, wherein the first direction is consistent with a direction in which the delivery target has a largest opening size.

6. The parcel dropping method of claim 4, further comprising: after the conveying device passes

by the delivery target, operating the conveying device to turn 90° or 180° along an arc when the conveying device is in motion so that the conveying device returns to a pickup region.

7. The parcel dropping method of claim 1 or 2, wherein the conveying device moves towards the delivery target in a first direction, and returns to a pickup region in a second direction that is different from the first direction after delivering the parcel.

8. The parcel dropping method of claim 1 or 2, wherein the conveying device moves towards the delivery target along a first arc-shaped curve, and returns to a pickup region along a second arc-shaped curve after delivering the parcel.

9. The parcel dropping method of claim 8, wherein the first arc-shaped curve and the second arc-shaped curve form an axisymmetric structure.

10. The parcel dropping method of claim 2, further comprising:

in condition that the condition is not satisfied, operating the conveying device to stop moving and deliver the parcel to the delivery target when the conveying device is stationary.

11. The parcel dropping method of claim 1, before the delivering, by the conveying device, the parcel to the delivery target, determining whether a delivering instruction for delivering the parcel is received; and

wherein the delivering, by the conveying device, the parcel to the delivery target after the conveying device moves to a delivery region comprises:

in condition that the delivering instruction is received, delivering, by the conveying device, the parcel to the delivery target after the conveying device moves to the delivery region.

12. An item sorting system, comprising:

at least one conveying device;

a parcel supply region, which is configured to distribute a to-be-sorted item;

a conveying region, which is configured for the at least one conveying device to move inside,

a parcel dropping region, wherein the parcel dropping region comprises a plurality of sorting targets, and

wherein the at least one conveying device is configured to convey the to-be-sorted item through the conveying region, and the at least one conveying device is further configured to deliver the to-be-sorted item to a corresponding sorting target of the plurality of sorting target in the parcel

dropping region when the conveying device is at a determined delivery speed in a determined delivery distance, wherein the determined delivery distance and the determined delivery speed are calculated according to a size parameter of a to-be-delivered parcel and a size parameter of the delivery target.

13. The item sorting system of claim 12, further comprising: a control system, wherein the control system is configured to determine whether the parcel dropping region satisfies a condition for delivering the to-be-sorted item when the conveying device is in motion; and

wherein in condition that the condition is satisfied, the control system is configured to transmit a delivering instruction, so that the conveying device delivers the to-be-sorted item to the corresponding sorting target in the parcel dropping region when the conveying device is in motion.

14. The item sorting system of claim 13, further comprising a turning region, wherein after the conveying device passes by the corresponding sorting target and reaches the turning region, the conveying device turns 90° or 180° along an arc when the conveying device is in motion so that the conveying device returns to a pickup region.

15. The item sorting system of claim 12, wherein the conveying device is further configured to: determine whether the parcel dropping region satisfies a condition for delivering the to-be-sorted item when the conveying device is in motion, and in condition that the condition is satisfied, deliver the to-be-sorted item to the corresponding sorting target in the parcel dropping region when the conveying device is in motion.

16. A sorting robot, comprising:

a drive unit, which is configured to drive the sorting robot to move towards a delivery position after the sorting robot receives a parcel in a pickup region;

a delivery unit, which is configured to deliver the parcel to a delivery target at the delivery position; and

a control unit, which is configured to control the delivery unit to deliver the parcel to the delivery target at a determined delivery speed in a determined delivery distance, wherein the determined delivery distance and the determined delivery speed are calculated according to a size parameter of a to-be-delivered parcel and a size parameter of the delivery target.

17. The sorting robot of claim 16, further comprising:

a detection unit, which is configured to detect whether an obstacle exists at the delivery position.

18. The sorting robot of claim 16 or 17, wherein the control unit is configured after the sorting robot passes by the delivery target, to control the drive unit to drive the sorting robot to turn 90° or 180° along an arc when the sorting robot is in motion so that the sorting robot returns to the pickup region.