

Abstract

The present invention appropriately avoids an obstacle. This control method comprises: a step of moving a moving body according to a reference route; a step of causing a sensor to detect an obstacle located on a first direction side, which is a traveling direction of the moving body, when the moving body is moving according to the reference route; a step of setting an avoidance route if the obstacle is present on the first direction side; a step of moving the moving body according to the avoidance route; and a step of updating the avoidance route on the basis of the detection result of the obstacle by the sensor when the moving body is moving according to the avoidance route. In the step of updating the avoidance route, the updated avoidance route is set with a subgoal as a target position if the detection result of the obstacle by the sensor does not satisfy a predetermined condition, and is set with a position on the reference route as the target position if the detection result of the obstacle by the sensor satisfies the predetermined condition.