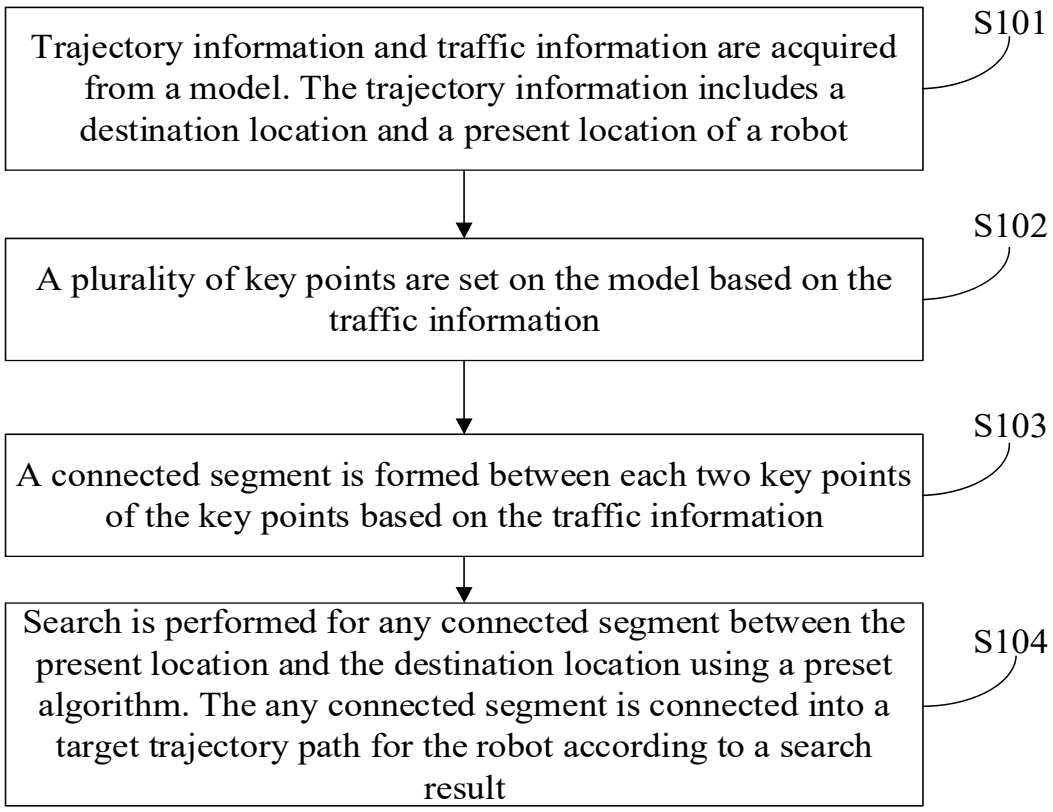
Trajectory information and traffic information are acquired from a model. The trajectory information includes a destination location and a present location of a robot
S101
A plurality of key points are set on the model based on the traffic information
S102
A connected segment is formed between each two key points of the key points based on the traffic information
S103
Search is performed for any connected segment between the present location and the destination location using a preset algorithm. The any connected segment is connected into a target trajectory path for the robot according to a search result
S104

FIG. 1

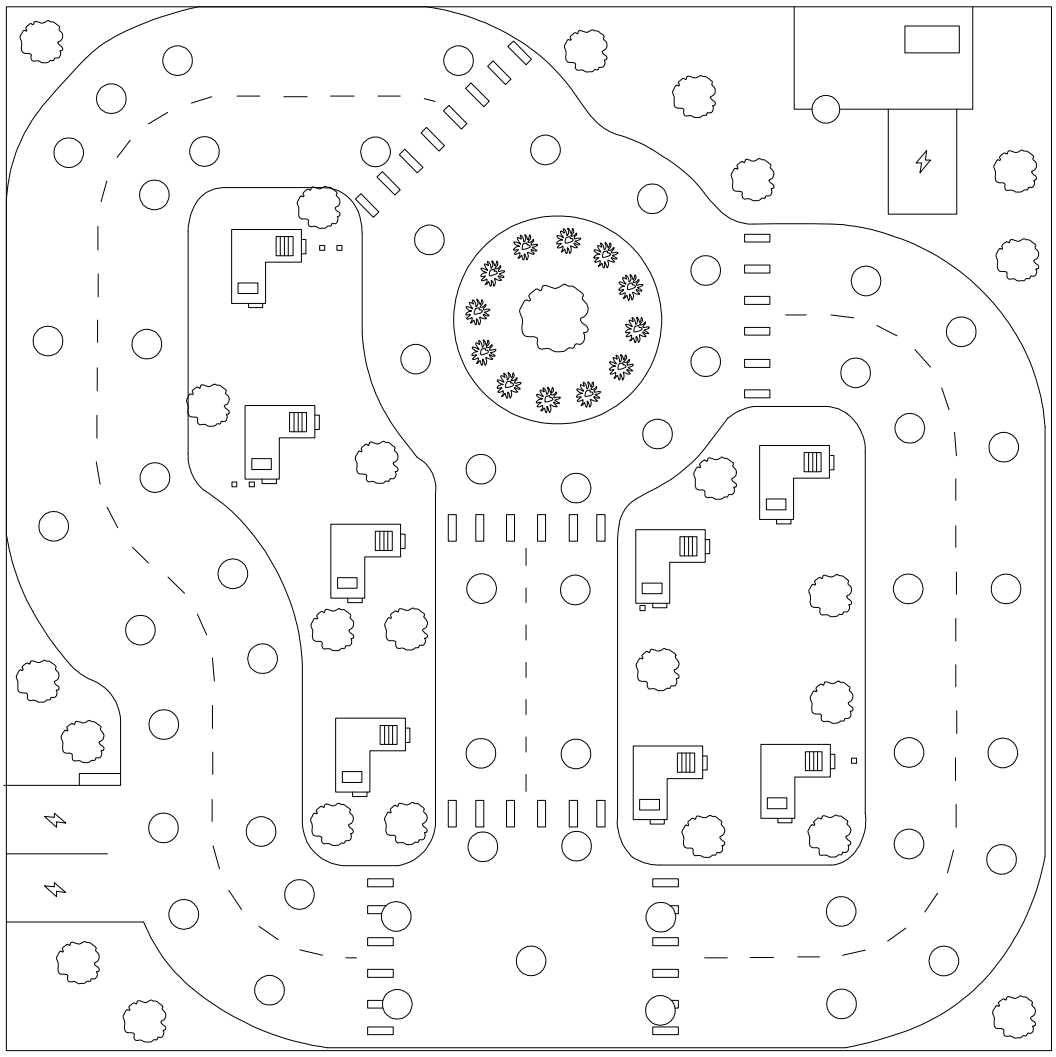

FIG. 2

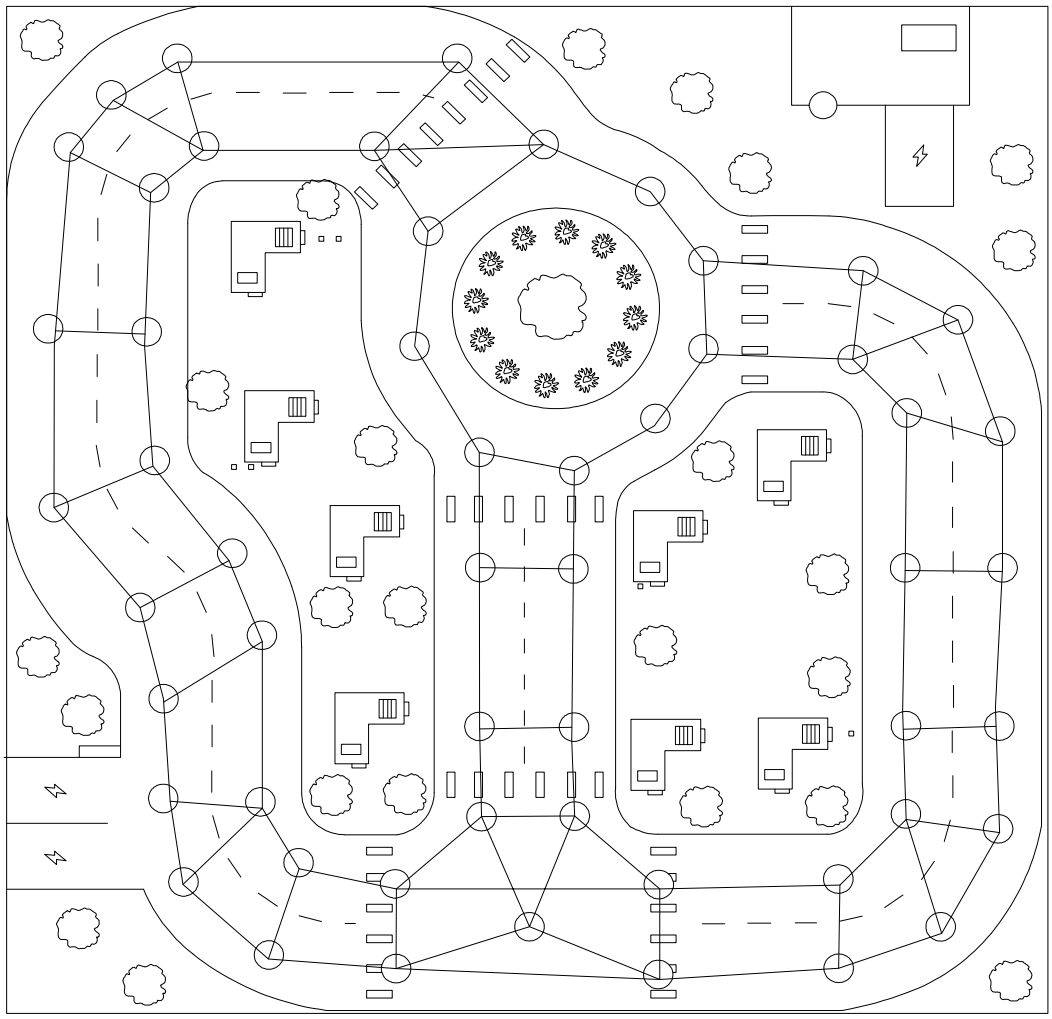

FIG. 3

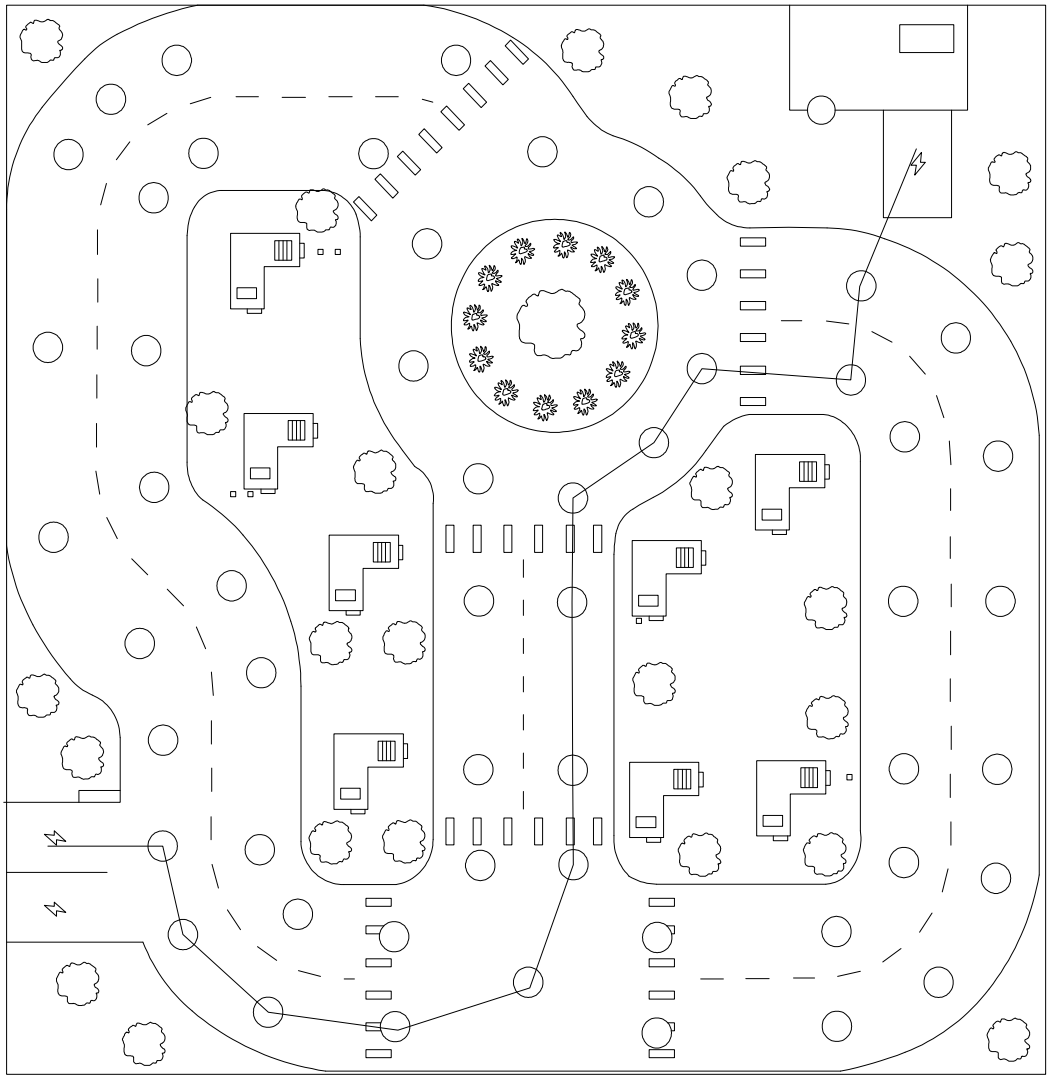

FIG. 4

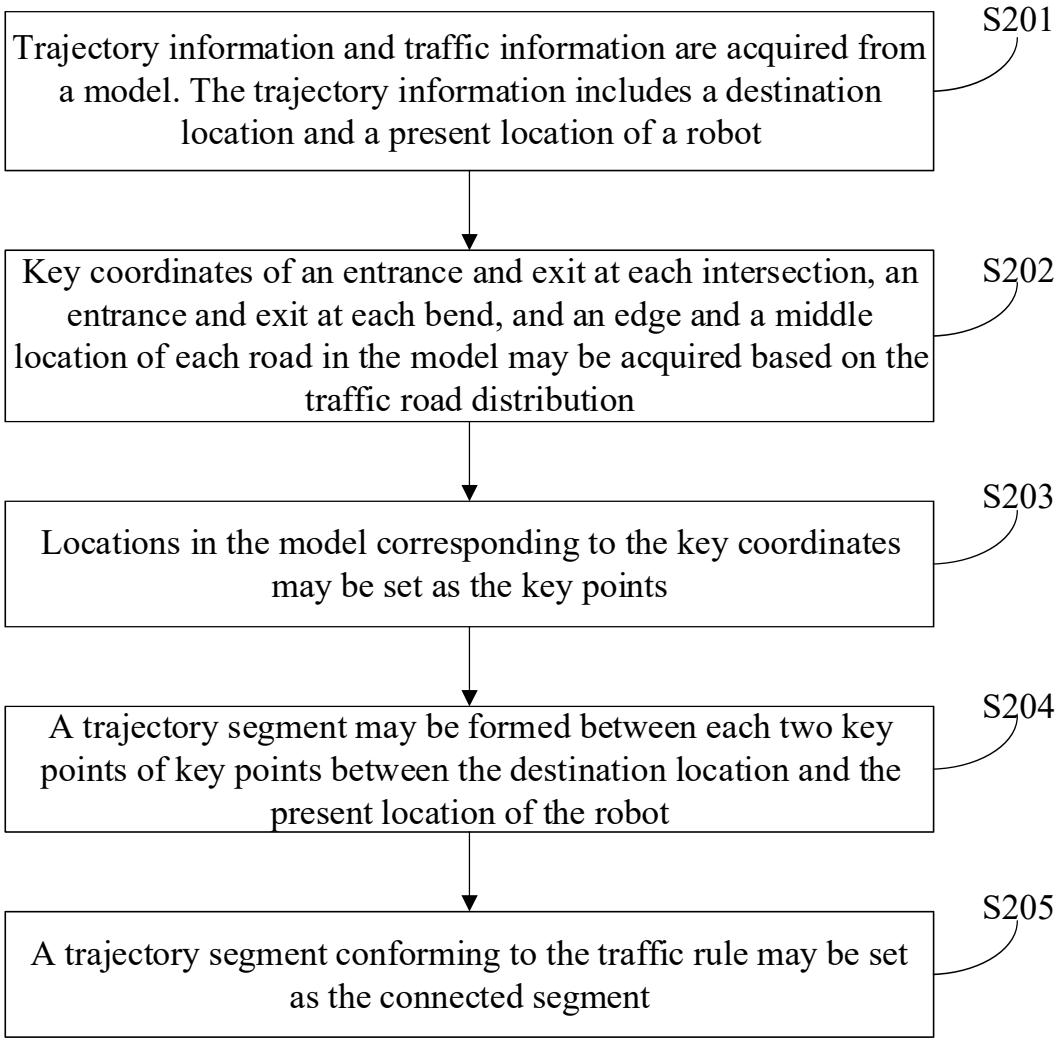
Trajectory information and traffic information are acquired from a model. The trajectory information includes a destination location and a present location of a robot
S201
Key coordinates of an entrance and exit at each intersection, an entrance and exit at each bend, and an edge and a middle location of each road in the model may be acquired based on the traffic road distribution
S202
Locations in the model corresponding to the key coordinates may be set as the key points
S203
A trajectory segment may be formed between each two key points of key points between the destination location and the present location of the robot
S204
A trajectory segment conforming to the traffic rule may be set as the connected segment
S205

FIG. 5

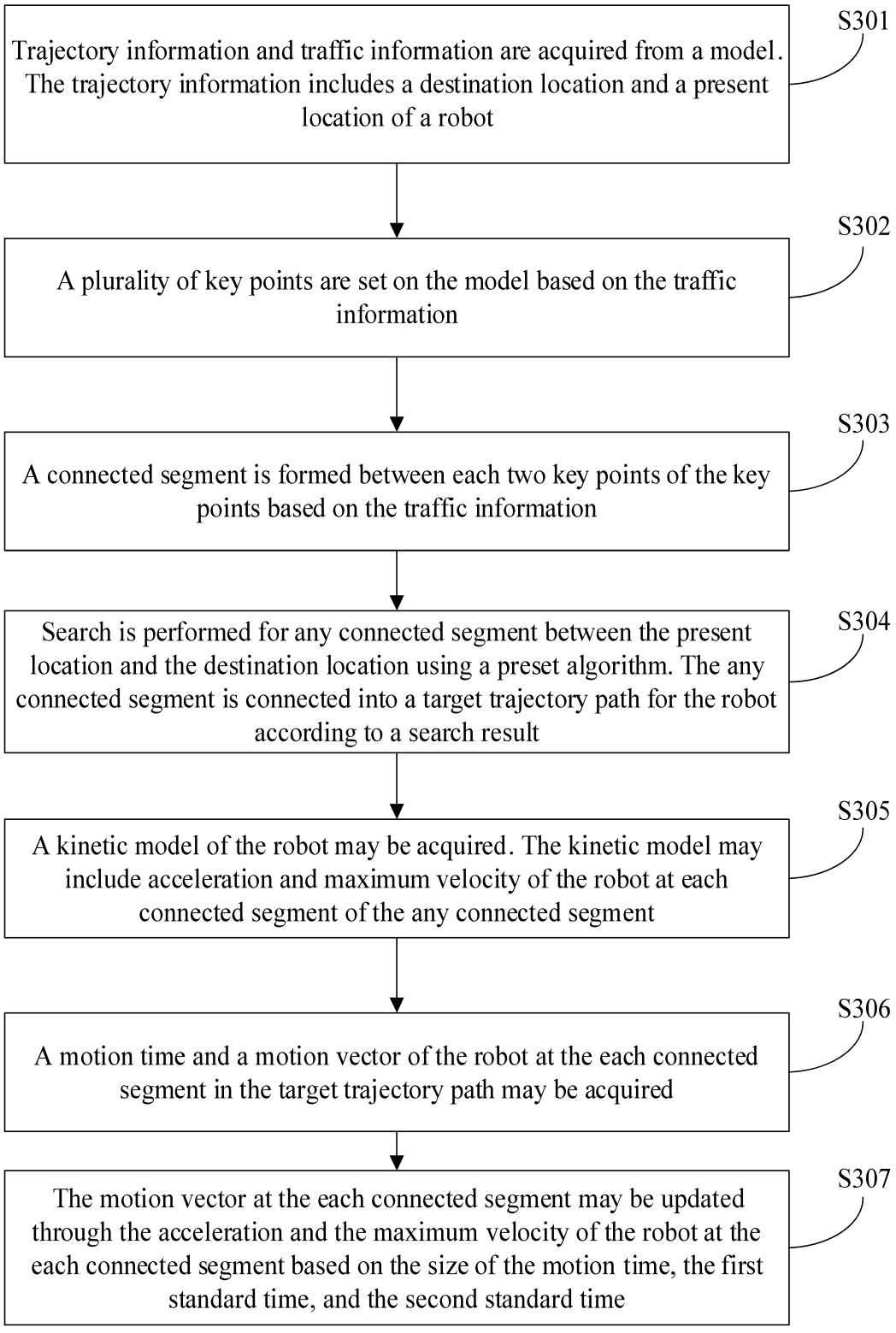
Trajectory information and traffic information are acquired from a model. The trajectory information includes a destination location and a present location of a robot
S301
A plurality of key points are set on the model based on the traffic information
S302
A connected segment is formed between each two key points of the key points based on the traffic information
S303
Search is performed for any connected segment between the present location and the destination location using a preset algorithm. The any connected segment is connected into a target trajectory path for the robot according to a search result
S304
A kinetic model of the robot may be acquired. The kinetic model may include acceleration and maximum velocity of the robot at each connected segment of the any connected segment
S305
A motion time and a motion vector of the robot at the each connected segment in the target trajectory path may be acquired
S306
The motion vector at the each connected segment may be updated through the acceleration and the maximum velocity of the robot at the each connected segment based on the size of the motion time, the first standard time, and the second standard time
S307

FIG. 6A

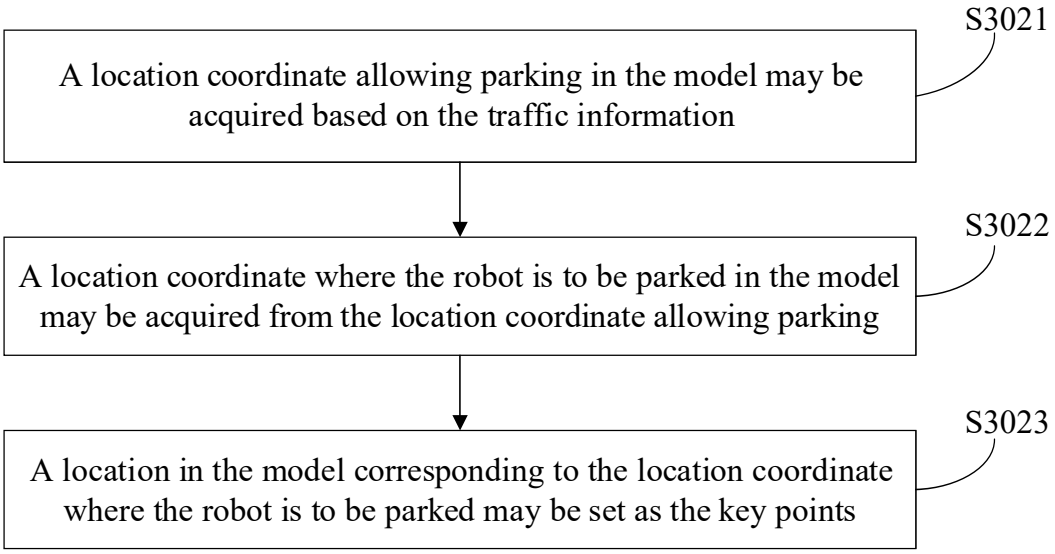
S3021
A location coordinate allowing parking in the model may be acquired based on the traffic information
S3022
A location coordinate where the robot is to be parked in the model may be acquired from the location coordinate allowing parking
S3023
A location in the model corresponding to the location coordinate where the robot is to be parked may be set as the key points

FIG. 6B

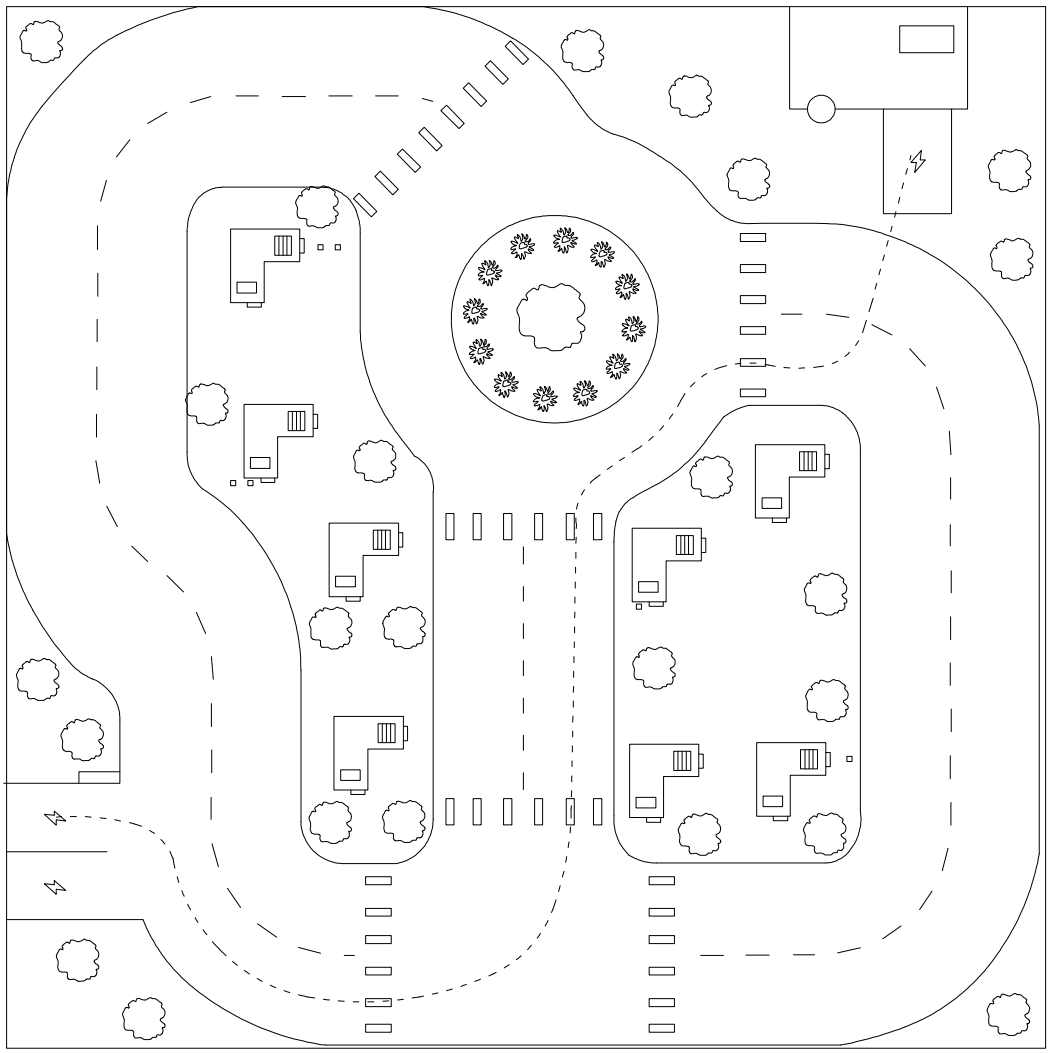

FIG. 7

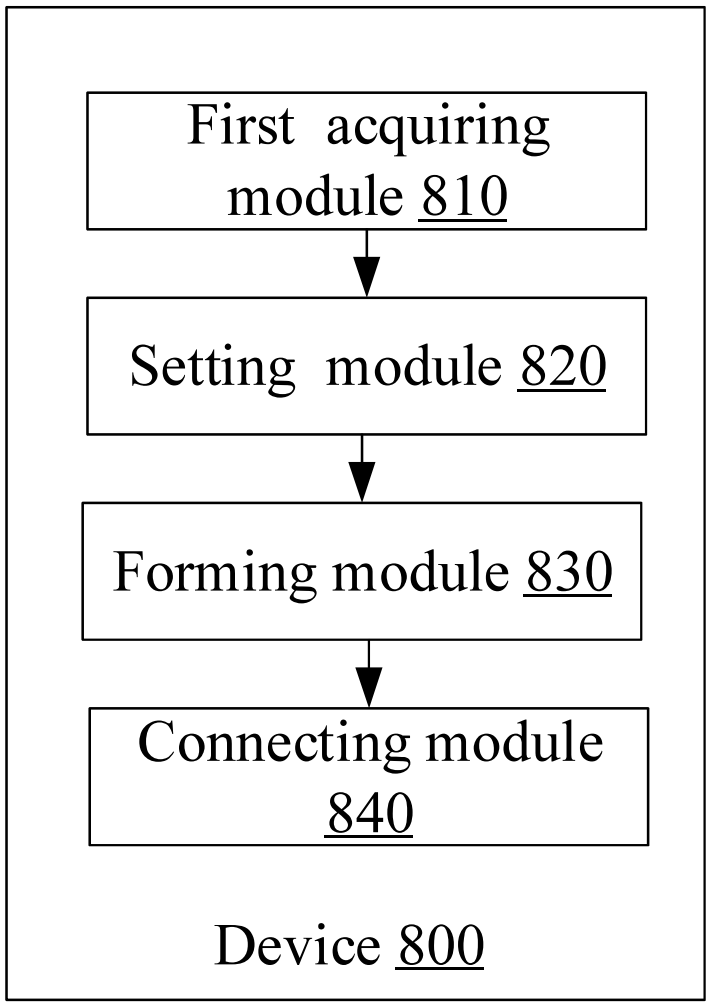
First acquiring module 810
Setting module 820
Forming module 830
Connecting module 840
Device 800

FIG. 8

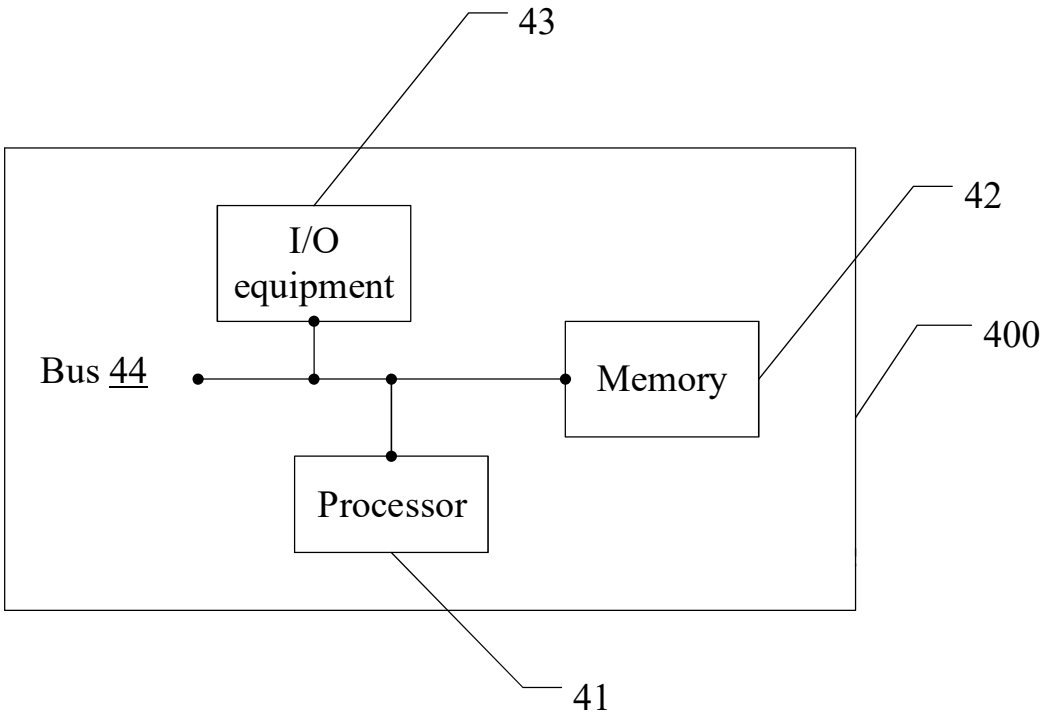

FIG. 9

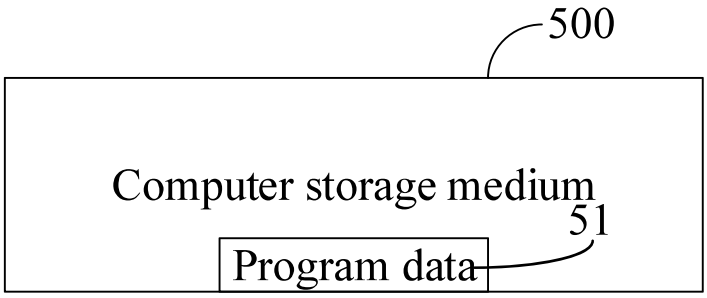

FIG. 10