

Abstract

The present invention makes it possible to avoid obstacles appropriately. This control method is for controlling a moving body that moves automatically, the method comprising: a step for moving the moving body along a reference path; a step for causing a sensor provided on the moving body to detect an obstacle located on the side toward a first direction, which is the traveling direction of the moving body, while the moving body is moving along the reference path; a step for, when an obstacle exists on the side toward the first direction, setting an avoidance path that extends in the first direction while avoiding the obstacle; a step for moving the moving body along the avoidance path; a step for generating an updated avoidance path, which is another avoidance path that satisfies a predetermined condition, while the moving body is moving along the original avoidance path; and a step for, if the updated avoidance path that satisfies the predetermined condition cannot be generated, retreating the moving body in a second direction opposite to the first direction.