

ABSTRACT

The present invention relates to a blind walking control method of a multi-legged walking robot and a robot using same, wherein the method includes the steps of: swinging a first leg
5 toward a first touch-down position according to a trajectory determined on the basis of a flat ground; controlling a swing operation of the first leg so that the first leg lands on a second touch-down position different from the first touch-down position when a change in topography is detected during the swing operation
10 of the first leg; configuring topography information including the second touch-down position; and determining a trajectory for a swing operation of a second leg following the first leg on the basis of the configured topography information.

15 Fig. 3