

ABSTRACT

The present invention relates to a method for changing the walking mode of a walking robot having a plurality of legs, and a robot using same, the method comprising the steps of: in a first walking mode in which terrain is recognized on the basis of vision sensor information and a walking trajectory is determined accordingly, swinging a first leg toward a first touchdown position according to the trajectory determined on the basis of the vision sensor information; and a step of changing to a second walking mode in which a walking trajectory is determined on the basis of flat terrain without using the vision sensor information if a change in terrain, different from the terrain recognized on the basis of the vision sensor information, is detected during the swinging motion of the first leg, wherein, in the second walking mode, terrain information is constructed using the actual landing position of the first leg, and a trajectory for the swinging motion of a second leg following the first leg is determined on the basis of the constructed terrain information.

Fig. 14