Simultaneous Evolution of Morphology and Locomotion of Soft Robots by Novelty Search

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Introduction

Soft Robots

- Inspired by nature
- Completely soft bodies
- ► Capable of developing new kinds of locomotion







Soft robots can be actuated through air pressure tubes, environmental changes (temperature, pressure), even explosions.

Related Material



VoxCad Simulator (Hiller & Lipson, 2012)

- Created by Jonathan Hiller and Hod Lipson
- Voxel modeling and analyzing software
- Capable of developing new kinds of locomotion

Related Work I

Evolving virtual creatures (Sims, 1994)

- Rigid body parts, joints
- Evolution of the morphology and the control







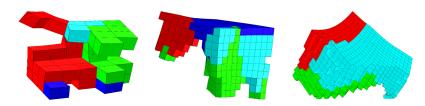
Evolving a diversity of virtual creatures through novelty search and local competition (Lehman & Stanley, 2011)

- Same experiment
- ▶ Novelty < Fitness</p>
- Novelty search with global competition has the best average fitness.

Related Work II

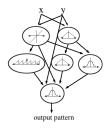
Evolving soft robots with multiple materials and a powerful generative encoding. (Cheney, MacCurdy, Clune, & Lipson, 2013)

- Generative encoding, Compositional pattern-producing network, CPPN.
- ▶ Neuroevolution of augmenting topologies, NEAT.



Compositional pattern-producing network

- Similar to artificial neural networks
- Different set of activation functions



- Produce symmetrical and repetitive patterns
- Appropriate for problems with geometrical structure (Board games).

References

- Cheney, N., MacCurdy, R., Clune, J., & Lipson, H. (2013).

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- Hiller, J., & Lipson, H. (2012). Dynamic simulation of soft heterogeneous objects. arXiv preprint arXiv:1212.2845.
- Lehman, J., & Stanley, K. O. (2011). Evolving a diversity of virtual creatures through novelty search and local competition. In *Proceedings of the 13th annual conference on genetic and evolutionary computation* (pp. 211–218).
- Sims, K. (1994). Evolving virtual creatures. In *Proceedings of the* 21st annual conference on computer graphics and interactive techniques (pp. 15–22).