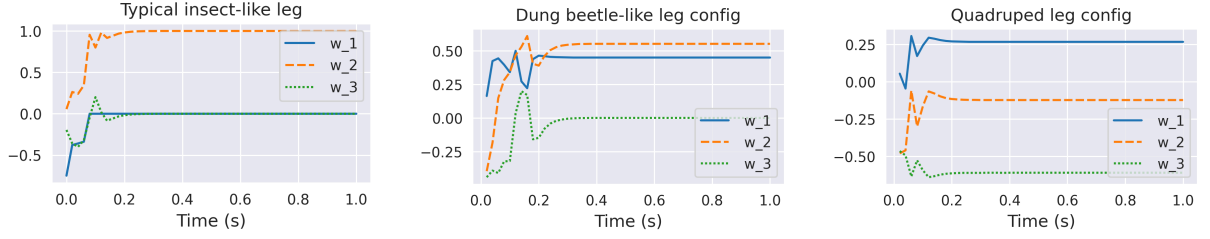


Supplementary Materials

Rapid Innate Learning Mechanism for Generic Morphologically Adaptive Legged Locomotion

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Supplementary Figures



(a) Typical insect-like leg. (b) Dung beetle-like leg. (c) Quadruped-like leg.

Figure 1: Weights learning of the joint-torque contribution learning.

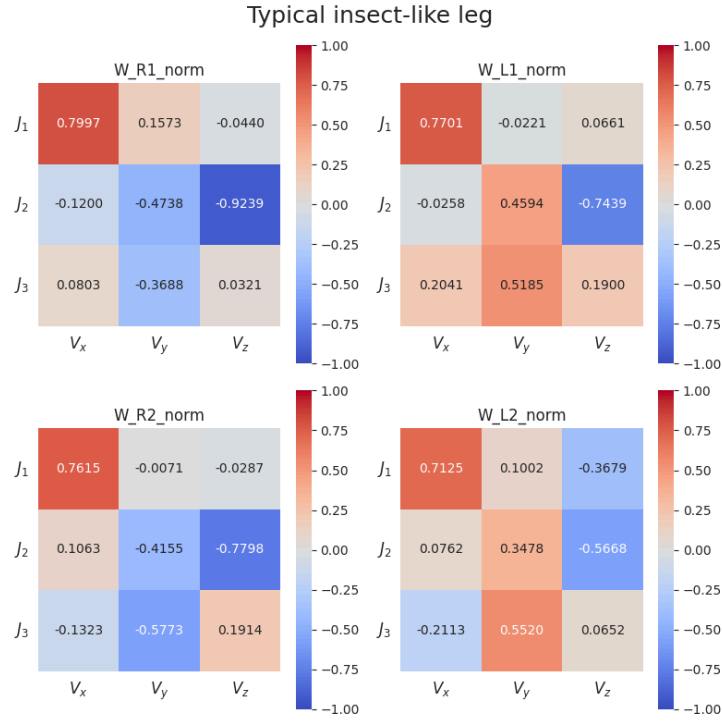


Figure 2: Normalized weight of the 4 legs robot with typical insect-like leg configuration from rapid innate learning of the multi-legged experiment.

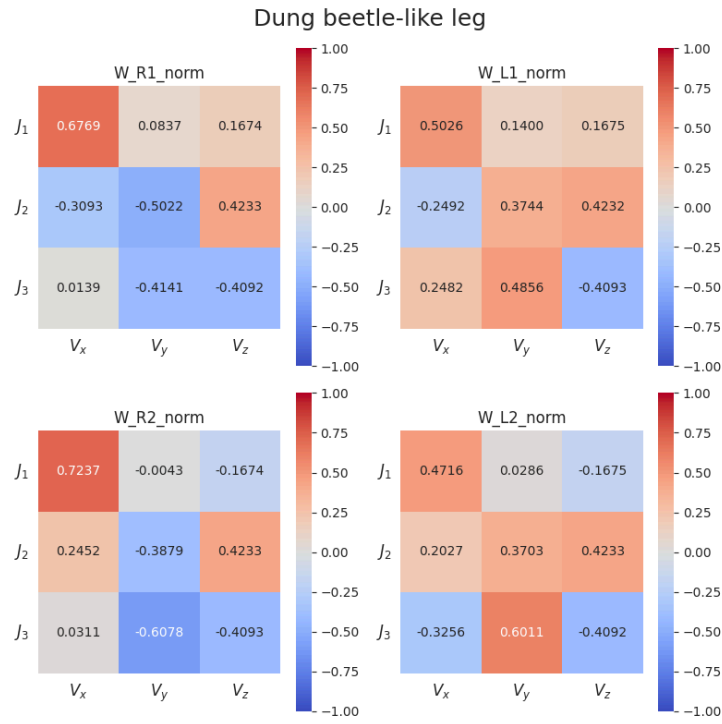


Figure 3: Normalized weight of the 4 legs robot with dung beetle-like leg configuration from rapid innate learning of the multi-legged experiment.

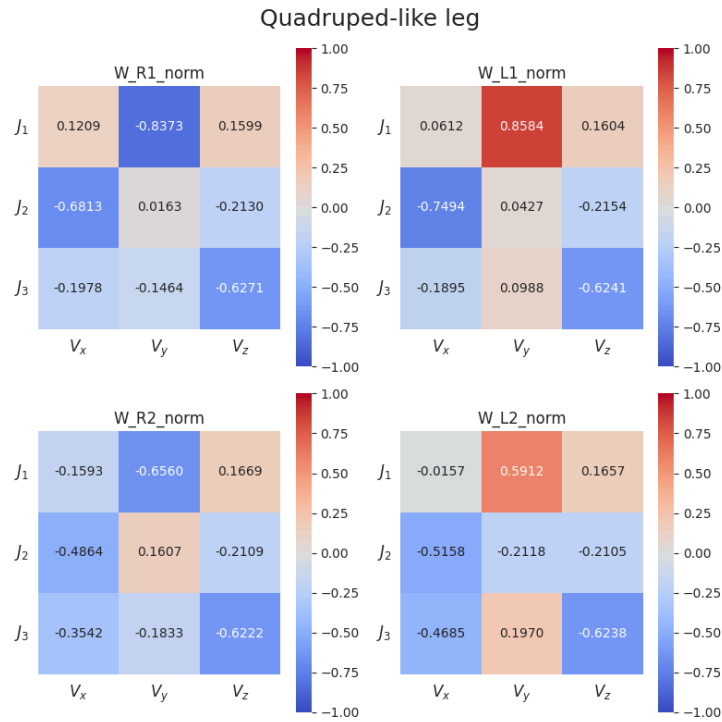


Figure 4: Normalized weight of the 4 legs robot with quadruped-like leg configuration from rapid innate learning of the multi-legged experiment.

Hexapod robot

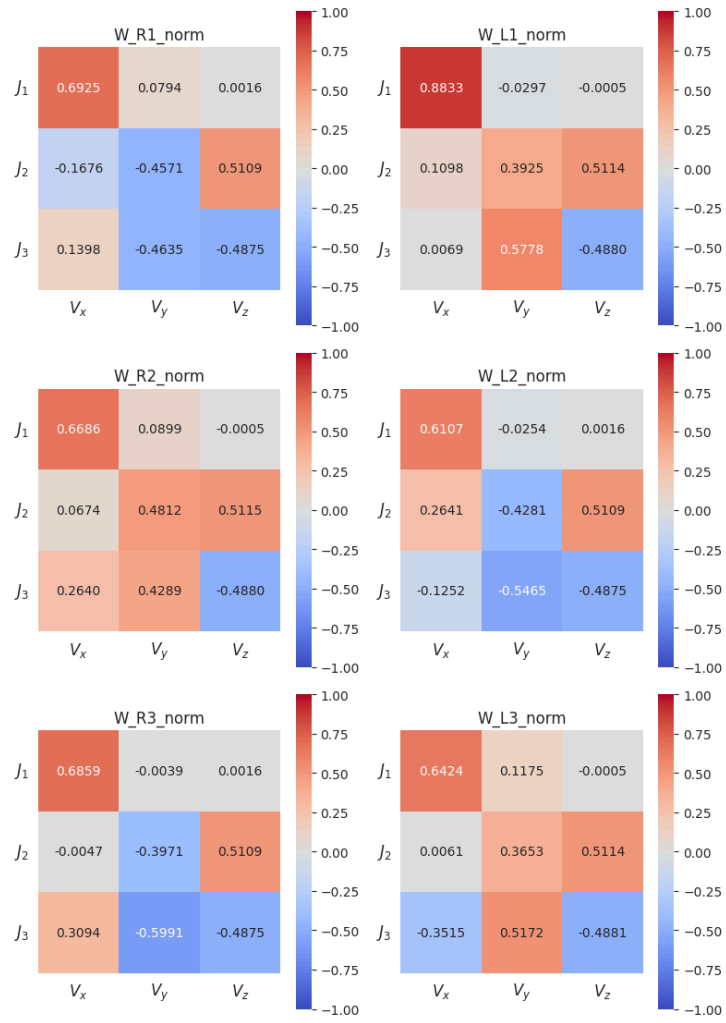


Figure 5: Normalized weight of the 6 legs hexapod robot rapid innate learning of the multi-legged experiment.