Generation	1	2	3
No. Legs	54	12	12
No. Segments	1	2	2
Segments joint	-	Pitch	Pitch, Yaw
Max. relative body-leg angle, deg	0	0 — 45	0, 15, 30, 45
Features	Wave propelled robot	Continuous changing relative body-leg angle mechanism	2 DoF segments joint mechanism
Withdraw	• Can't install sensors on legs • Low motor transmission efficiency	• Too complicated relative body-leg angle joint	• Small legs • Unnecessary yaw joint
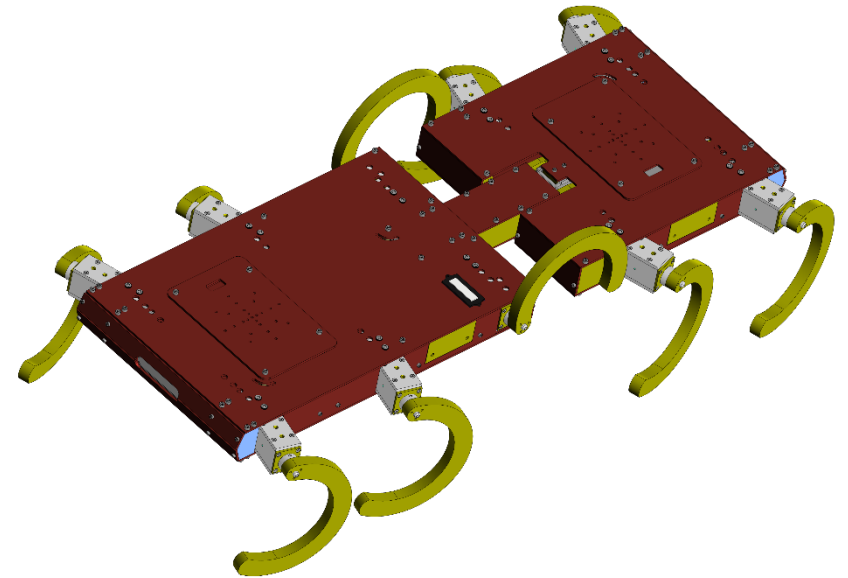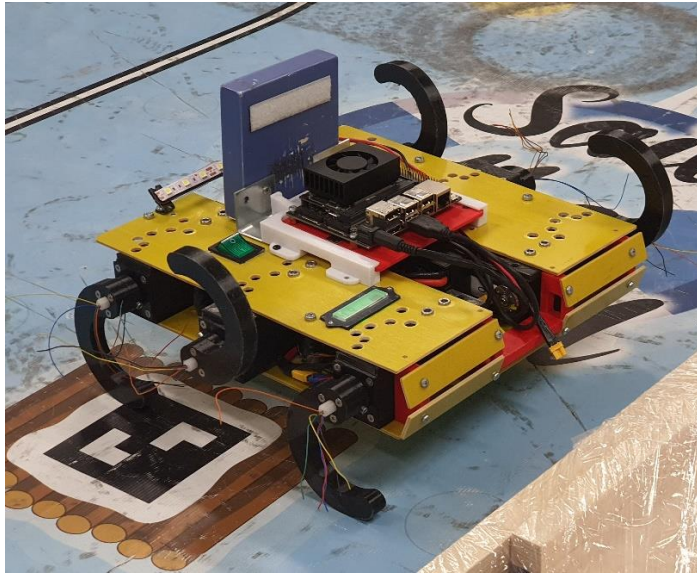
Generation	3+	4
No. Legs	6	10
No. Segments	1	2
Segments joint	-	Pitch
Max. relative body-leg angle, deg	0	0, 15
Features	Big legs	Biggest legs
Withdraw	• Still small legs • 1 segment	