|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  |  |  | |  | |
| 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 |  |