

(a) 2D Planar Locomotion Environments



(b) 3D Subequivariant Locomotion Environments

Table 1. Comparison in the problem setup. 2D-Planar Our 3D-SGRL

External Force NULL

Group

Symmetry

State Space	Range Initial Target	xoz -plane x^+ -axis x^+ -axis	3D space Arbitrary direction Arbitrary direction
Action Space	# Actuators DoF		3 per joint 3 per joint

Gravity \vec{g} , Target \vec{d}

 $O_{\vec{g}}(3)$