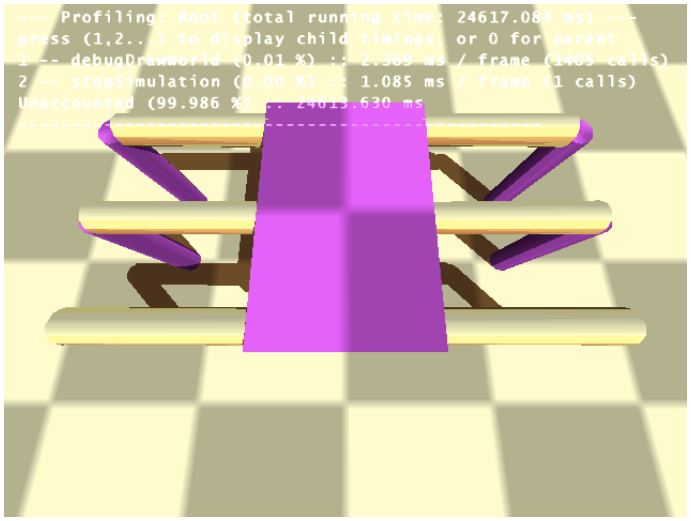
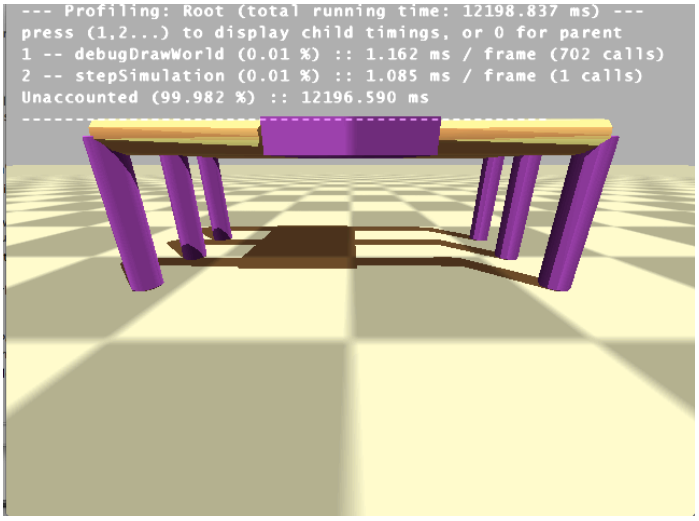
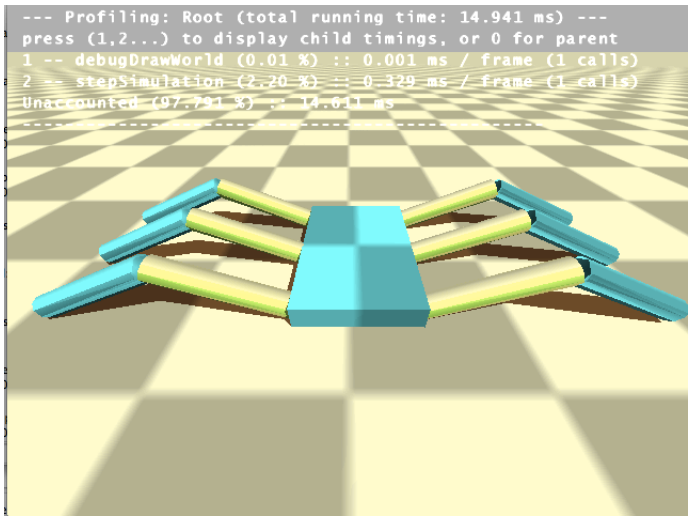
Brendan McOmber
CS 206 Final Project: Weekly Report 3





Figs 11.3a & 11.3b: Two legs added to each side of robot from the previous week's quadruped



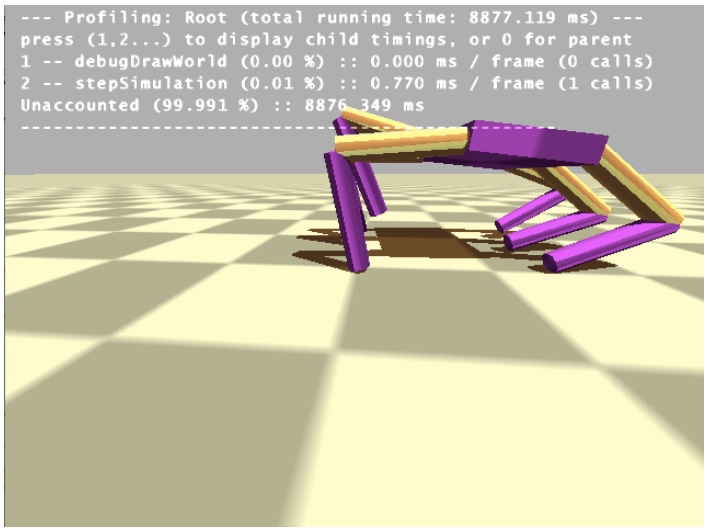


Fig 11.3c: Hexapod with proper joint angle limits
Fig 11.3d: Moving with random motor values

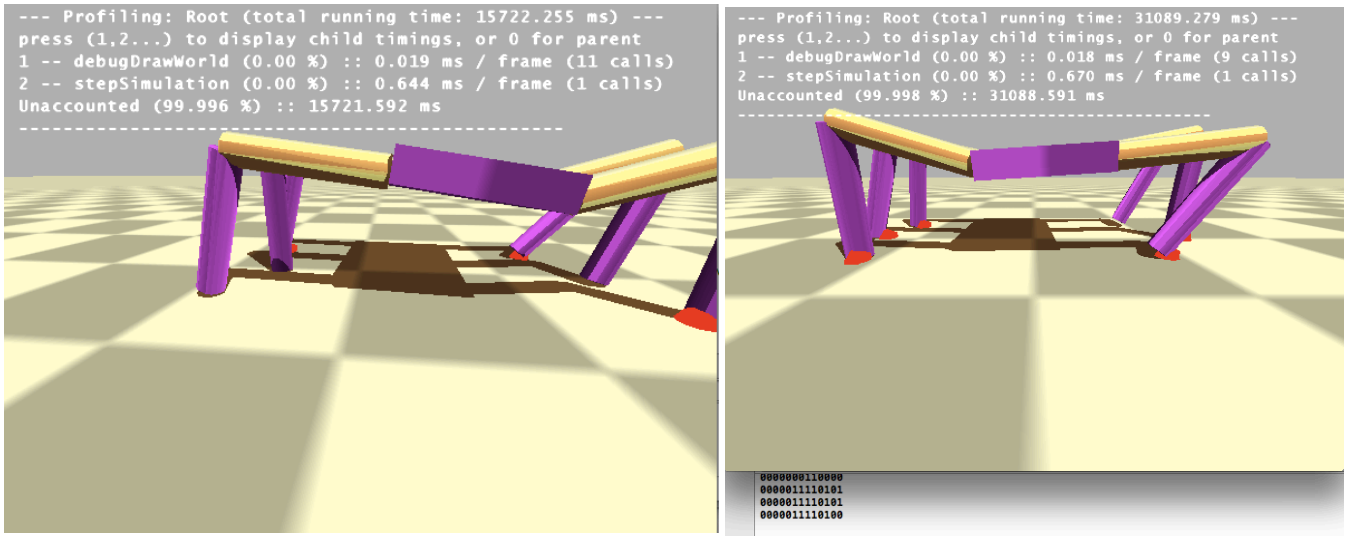


Fig 11.3e & 11.3f: Touch sensors firing on contact with ground

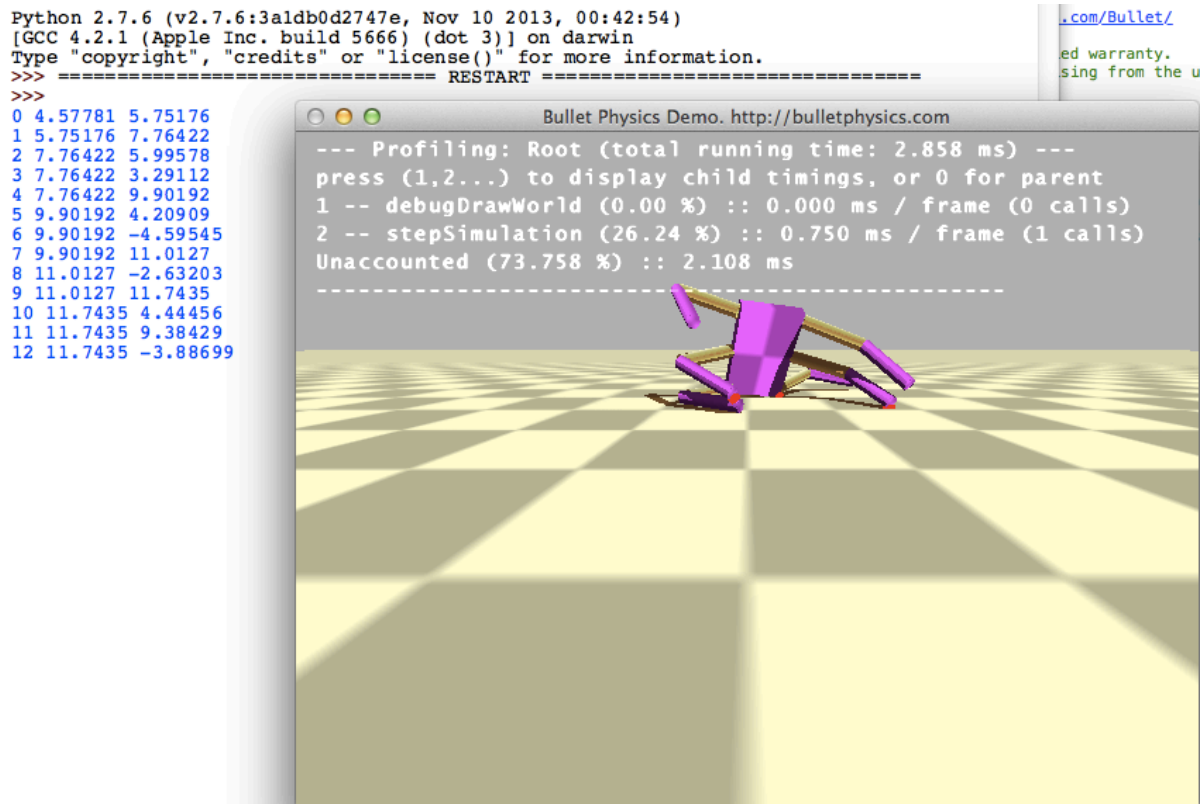


Fig 11.3g: Highly Fit hexapod moving into the screen

This past week I have been working on adding two more legs to my robot, so that it has three on each side. The code for my other two robots, the quadruped we created and the one that I made for weekly report #2, exist in their own separate directories. Now that I have the all three robots made, my main focus in the coming week will be to implement an evolutionary algorithm that punishes for movement involving contact of the main body rectangle to the ground, which is what my brief evolutionary runs have produced for the robots with legs on only two sides. I will apply this algorithm to all robots to keep only the morphology and corresponding number of neurons, motors and touch sensors different between them.