

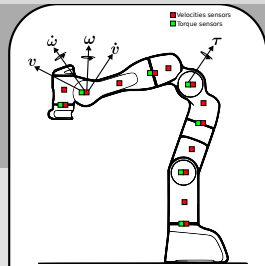
Requirements

First-Order Principles

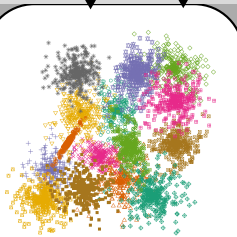
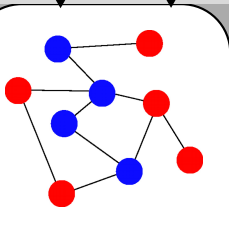
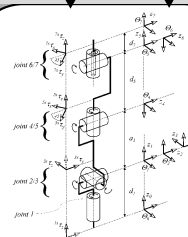
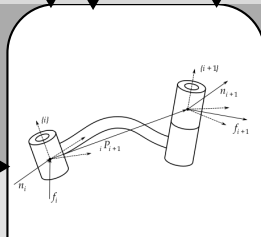
Sensing of \mathcal{K} Sensing of \mathcal{D}

Known

Unknown



Robot

 N
 A
 λ
 θ Data
clustering N
 A
 λ
 θ Topology
learning N
 A λ
 θ Morphology
learning N
 A
 λ
 θ Dynamics
learning N
 A
 λ
 θ

Body schema learning

 $\mathcal{S} = \{N, A, \lambda, \theta\}$