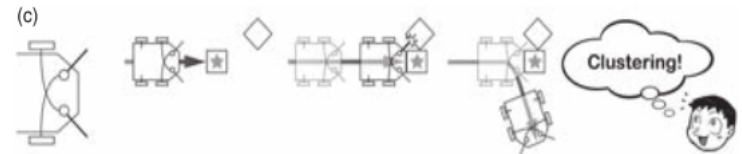
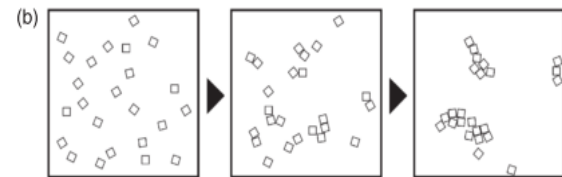
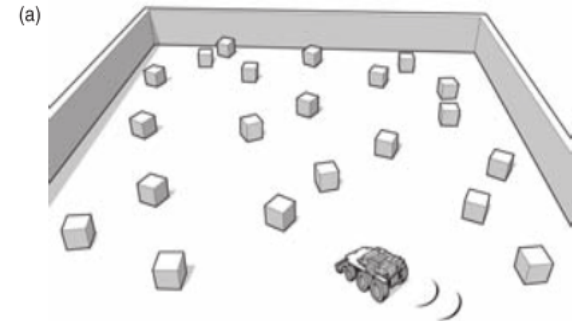


Kōan 1: “Swiss Robots” with adaptive morphology

- “Swiss Robots” depend on sensor morphology for performing a complex collective behavior (collecting boxes in piles) with extremely simple controllers and no explicit inter-robot communication
- What if the sensor morphology could be adapted by the robot’s controller, e.g. changing the pitch/yaw of the proximity sensors?
- Student could for example explore the ability to collectively adapt to a given box size, to optimize behavior, or to show specialization.
- What if we introduce a slope?



*Do you have other ideas?
Feel free to be creative!*