

Automatic Gait Pattern Selection for Legged Robots

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- Propose the idea of **building gait pattern selection maps** using mixed-integer Optimal Control and supervised learning
- Index maps on **performance objectives** and **environment** models.
- Show that discovered *gait maps* exhibit **structural** properties (e.g., **trajectories in contiguous gait region** are **similar**).
- Exploit these properties to **speed up the computation** by **warm-starting**

