

# Lecture 2. Embodiment: Concept and Models



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# Intelligence:

Hard to agree on definitions, arguments

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- **necessary and sufficient conditions?**
- **are robots, ants, humans intelligent?**

more productive question:

**“Given a behavior of interest, how to implement it?”**

# Successes and failures of the classical approach

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successes

**applications (e.g.  
Google)**

**chess**

**manufacturing**

(“controlled” artificial  
worlds)

failures

**foundations of  
behavior**

**natural forms of  
intelligence**

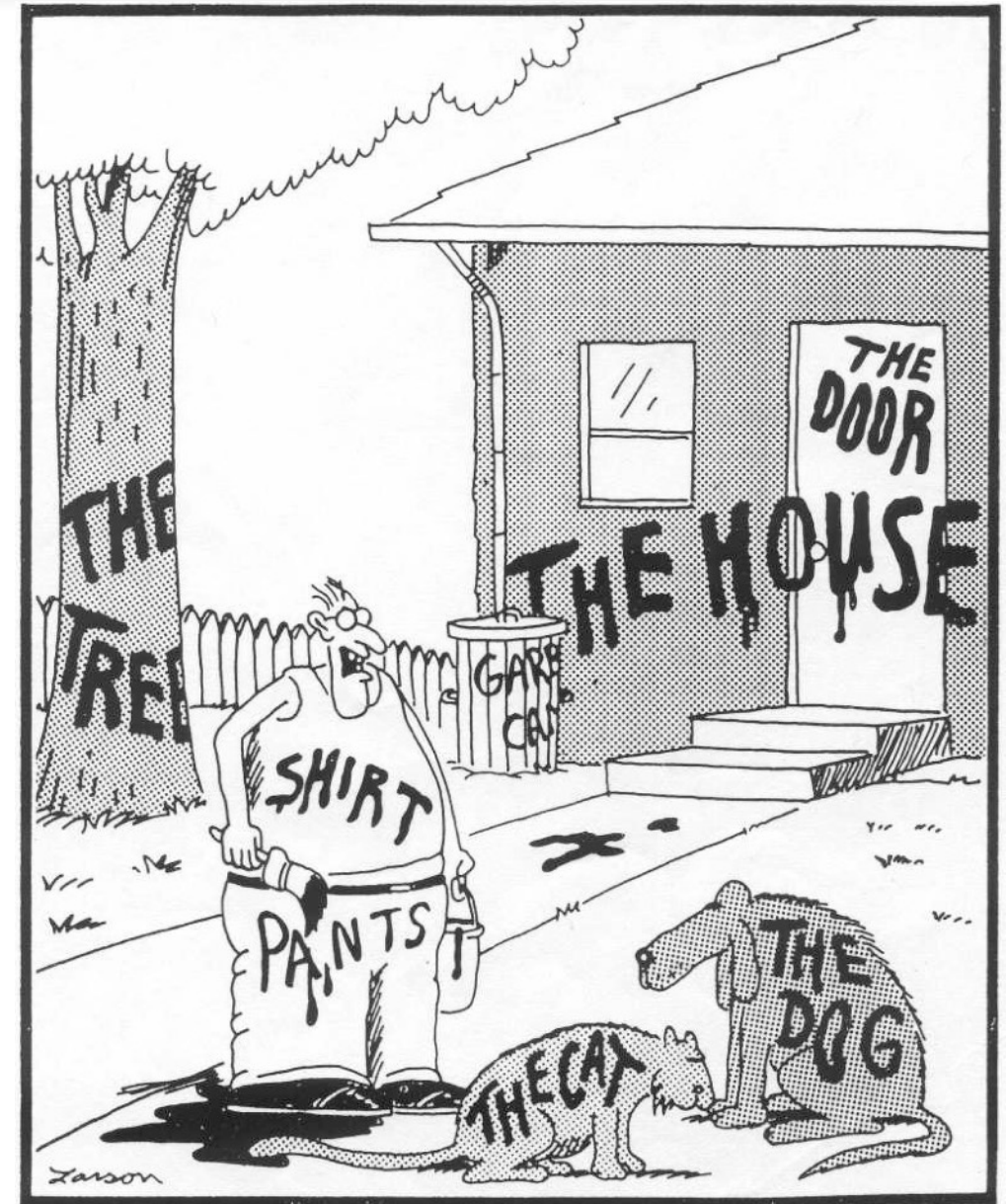
**interaction with real  
world**

# The “symbol grounding” problem

real world:  
doesn't come  
with labels ...

How to put the  
labels??

Gary Larson



"Now! ... That should clear up  
a few things around here!"

# Two views of intelligence

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classical:  
**cognition as computation**



embodiment:  
**cognition emergent from sensory-  
motor and interaction processes**



# The need for an embodied perspective

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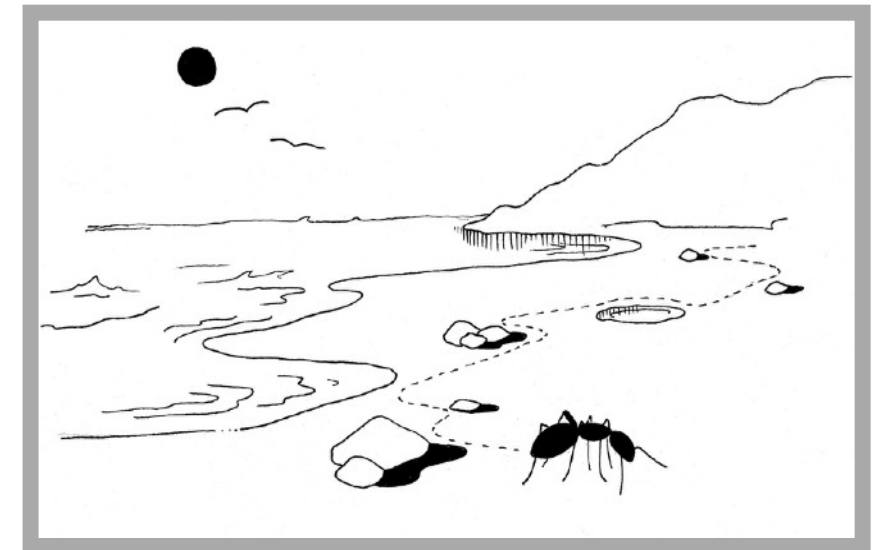
- **“failures” of classical AI**
- **fundamental problems of classical approach**
- **Wolpert’s quote: Why do plants not ...?  
(but...check...Barbara Mazzolai’s lecture...)**
- **Interaction with environment: always mediated by body**

# **“Frame-of-reference”**

## **Simon’s ant on the beach**

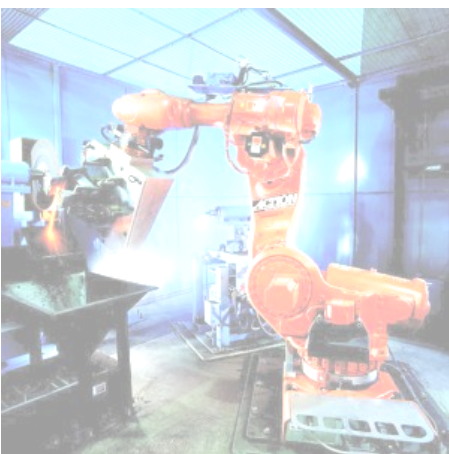
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- **simple behavioral rules**
- **complexity in interaction,  
not — necessarily — in brain**
- **thought experiment:  
increase body by factor of 1000**





# Industrial robots vs. natural systems



**robots**

principles:

- low precision
- compliant
- reactive
- coping with uncertainty

**humans**



➔ **no direct transfer of methods**



# Communication through interaction with

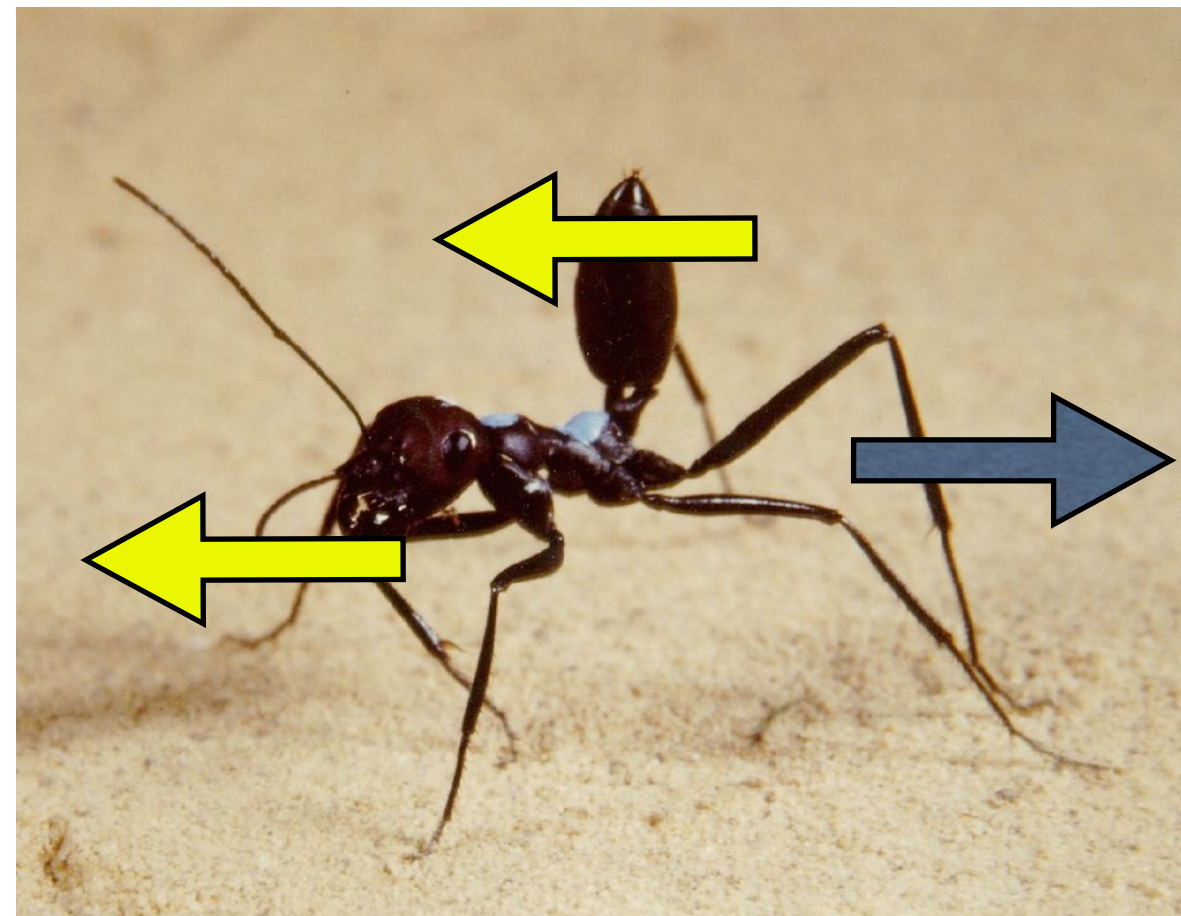
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- exploitation of interaction with environment

→ simpler neural circuits

angle sensors  
in joints

“parallel, loosely  
coupled  
processes”

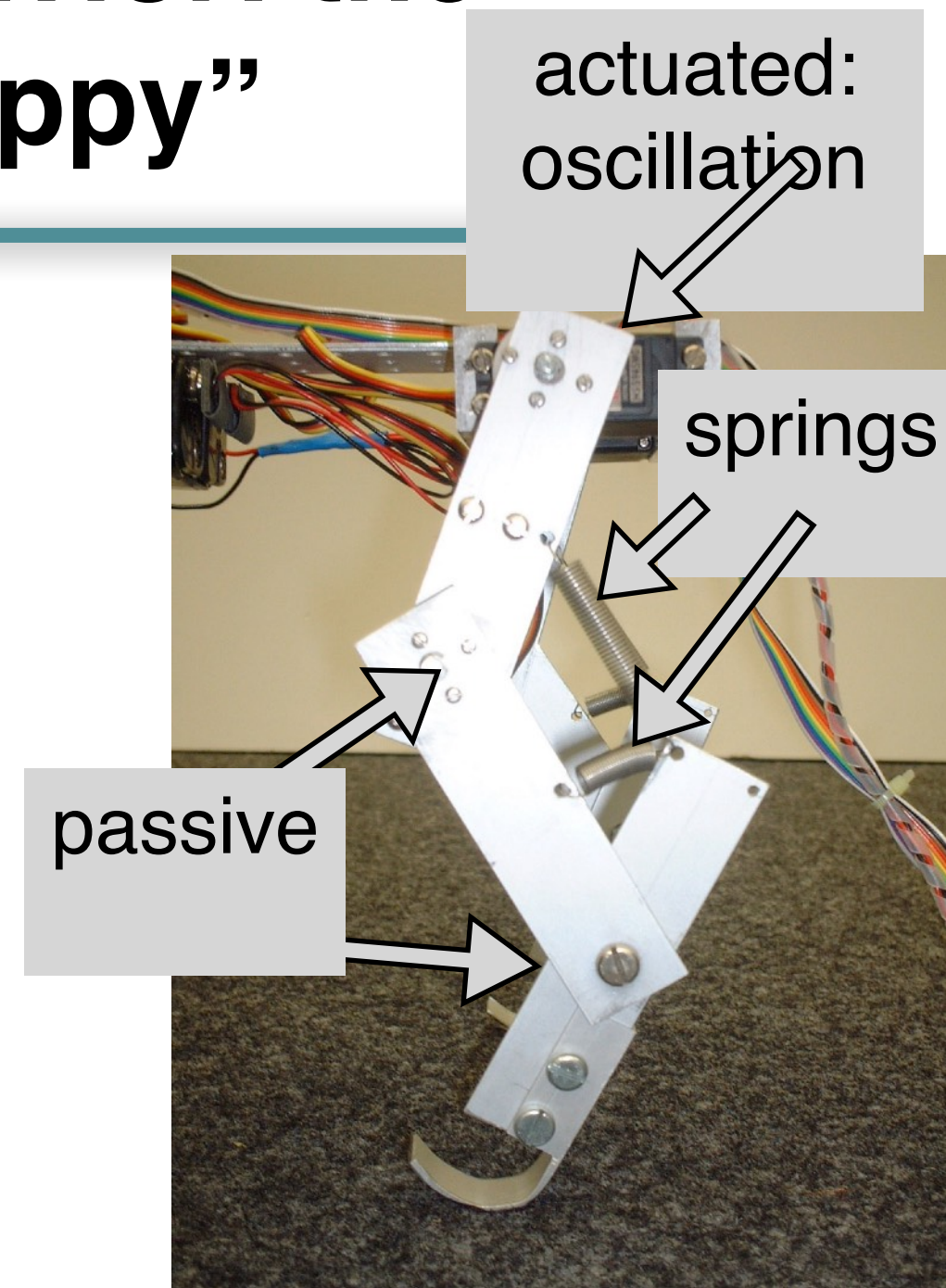


# Emergence of behavior: the quadruped “Puppy”

- **simple control (oscillations of “hip” joints)**
- **spring-like material properties (“under-actuated” system)**
- **self-stabilization, no sensors**
- **“outsourcing” of functionality**



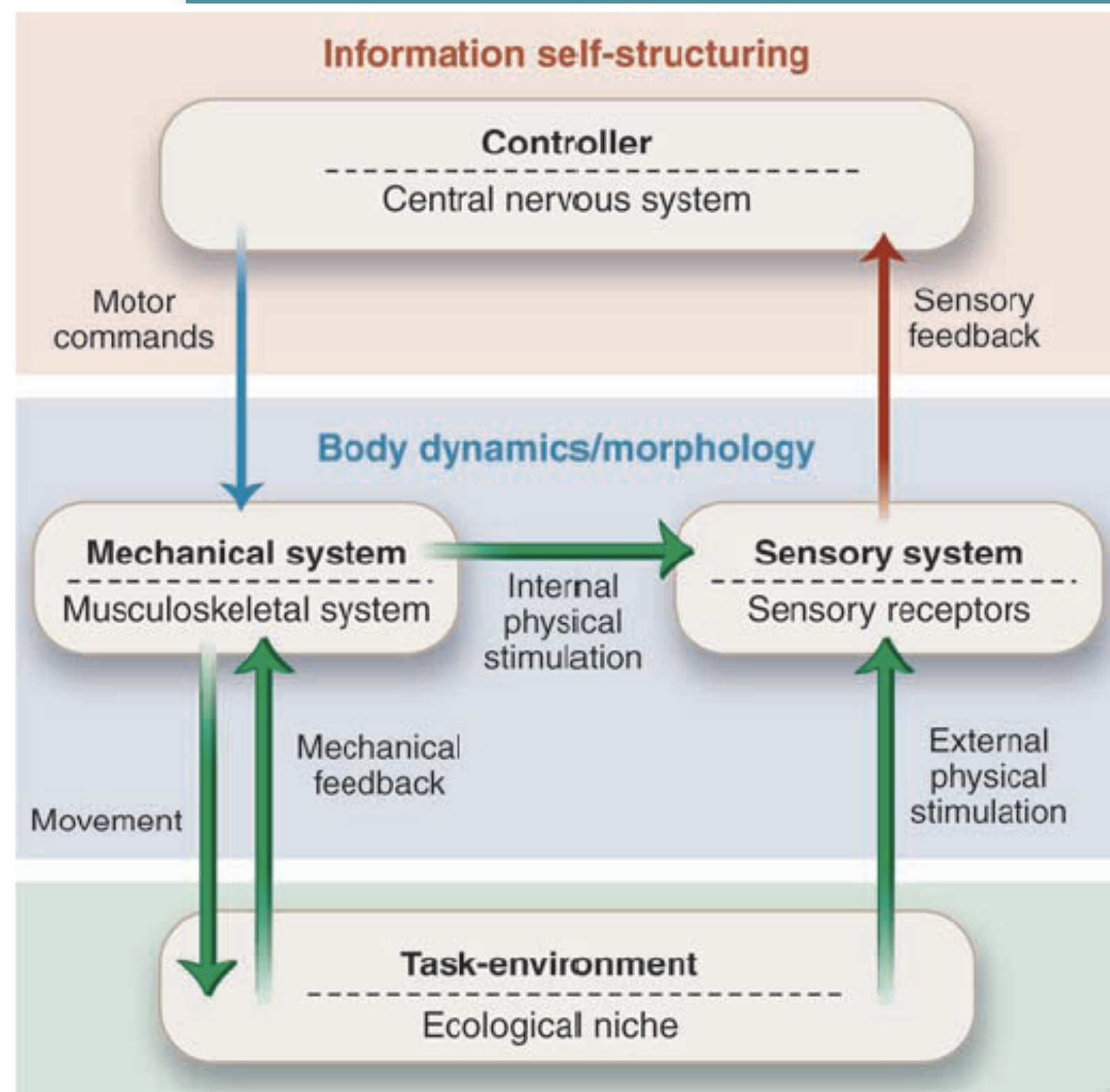
morphological  
computation



# Implications of embodiment

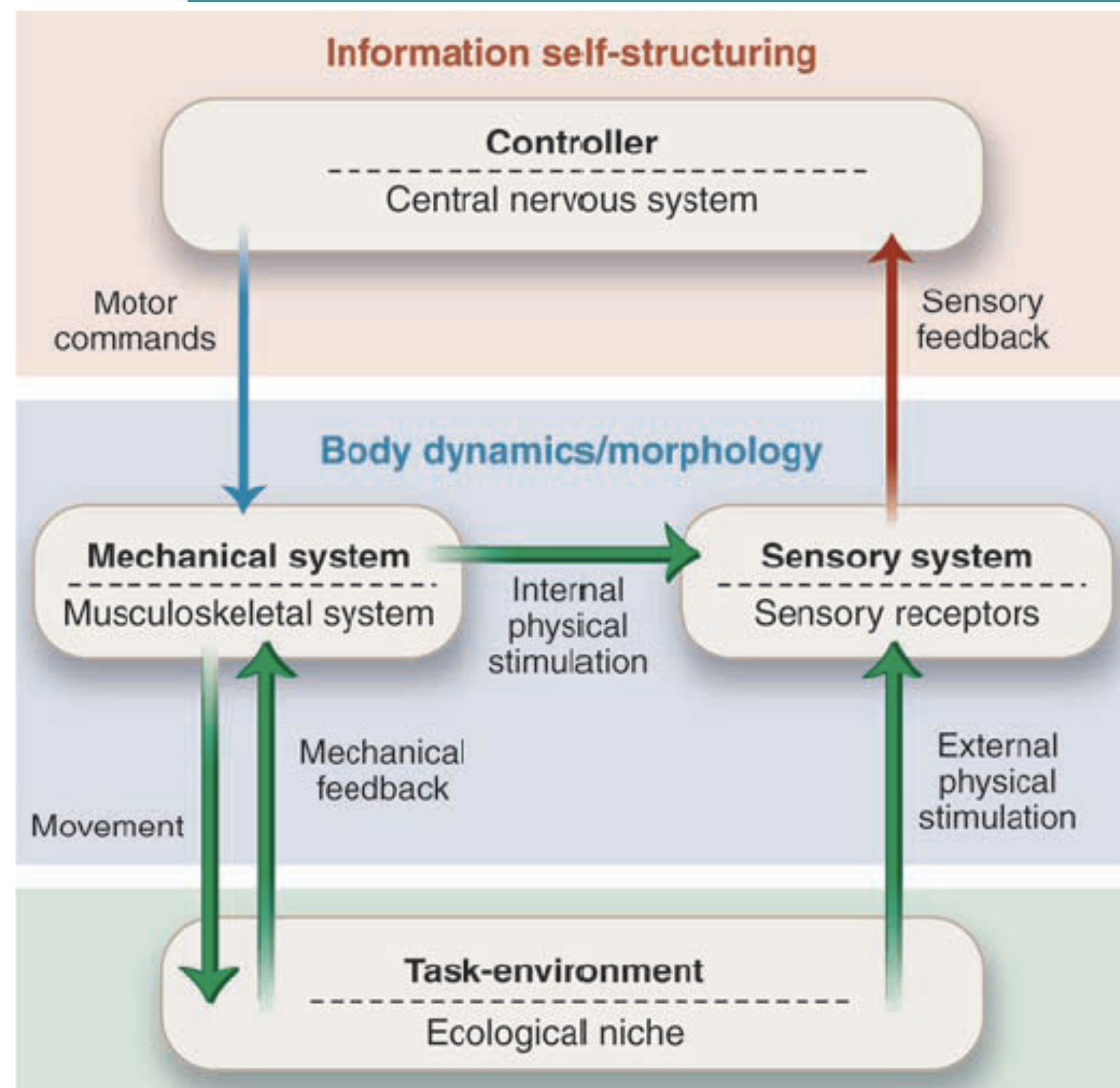
“Puppy”, But Also Crus

Pfeifer et al., Science,  
16 Nov. 2007





# Implications of embodiment



“Puppy”

which part of diagram is relevant?

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Pfeifer et al., Science,  
16 Nov. 2007