

Learning Human-like Locomotion Based on Biological Actuation and Rewards

Supplementary Material



Figure 1: Experimental results. From top to bottom: Ours (row 1), Dense energy (MET) only (row 2), Sparse energy (CoT) only (row 3), Without energy reward (row 4), Start with a double stance pose (row 5), Dense activation reward (row 6), Without muscle fiber length in observation (row 7)

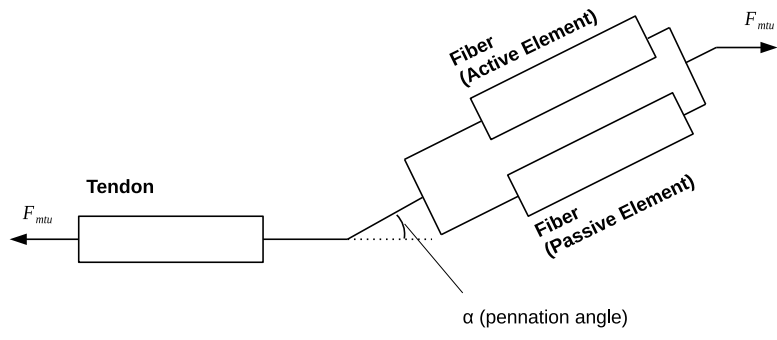


Figure 2: Hill-type muscle model