

Environmentally-Driven Morphogenesis of Reconfigurable Floating Robots using Markov Models: Supplementary Material

Nana Obayashi, Germain Meyer, Kai Junge & Josie Hughes

Supplementary Figure

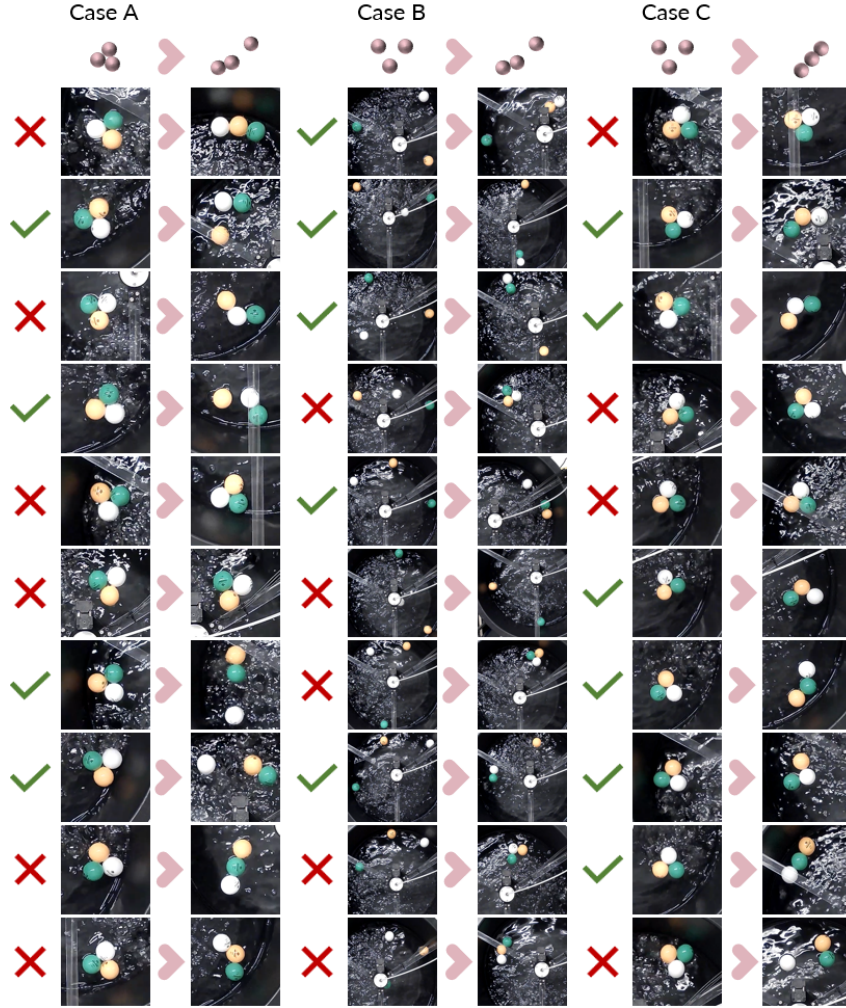


Figure S1. Snapshots of the start and end states from the experiment corresponding to Fig. 7c in the main manuscript. For each case, 10 consecutive open-loop control trials are conducted. For Case C, the experiments start from a clustered state from than a dispersed state, as there is a 100% probability of success to get to the clustered state with the control method found.

Supplementary Video

Supplementary Video 1 shows some deliberate state changes using the bubble wall for the system of floating balls, in real time. It shows partial and complete adhesion and de-adhesion.