

# MORPHOLOGICAL CONTROL AND COMPUTATION

## A DYNAMICAL SYSTEM APPROACH

Helmut Hauser

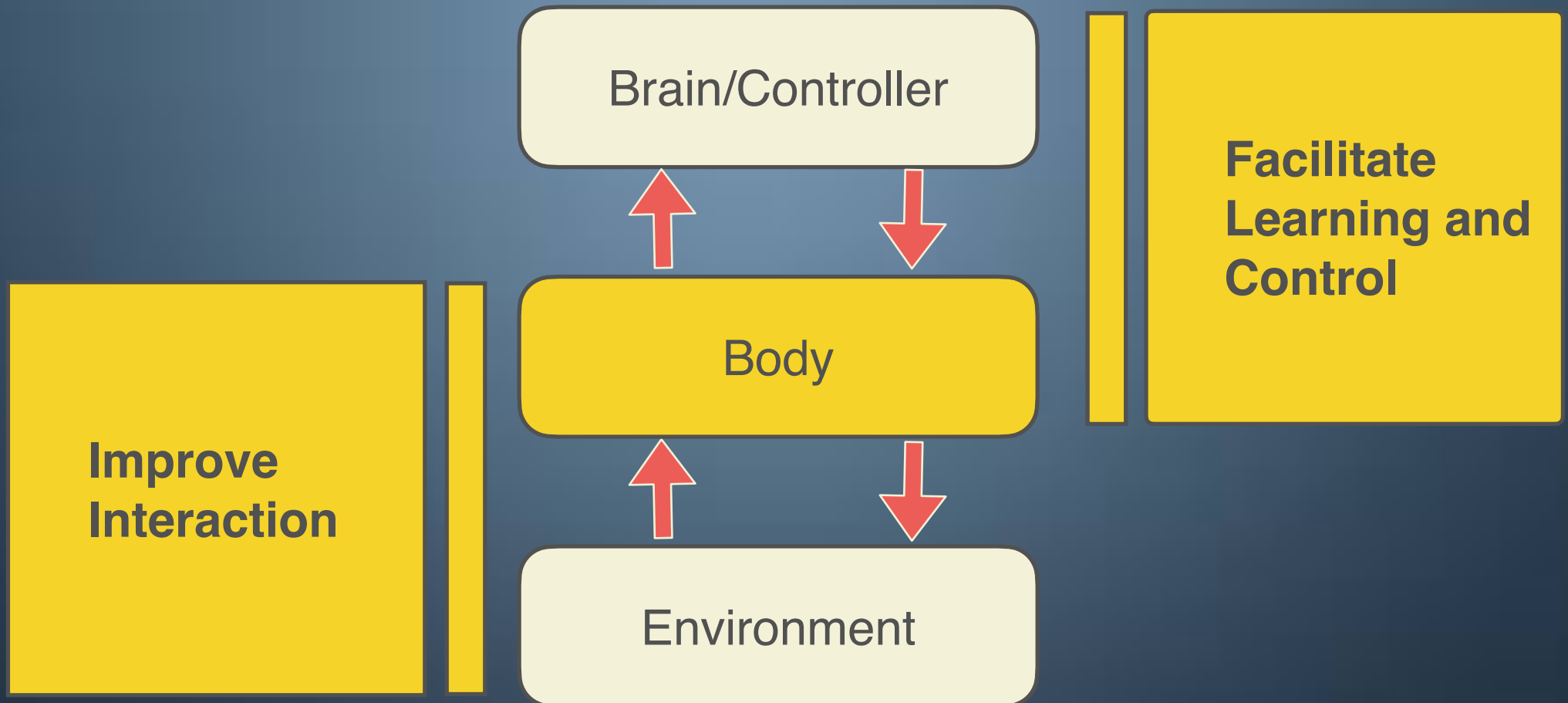
Department of Engineering Mathematics  
University of Bristol

[helmut.hauser@bristol.ac.uk](mailto:helmut.hauser@bristol.ac.uk)

 [@morphcomp](https://twitter.com/morphcomp)

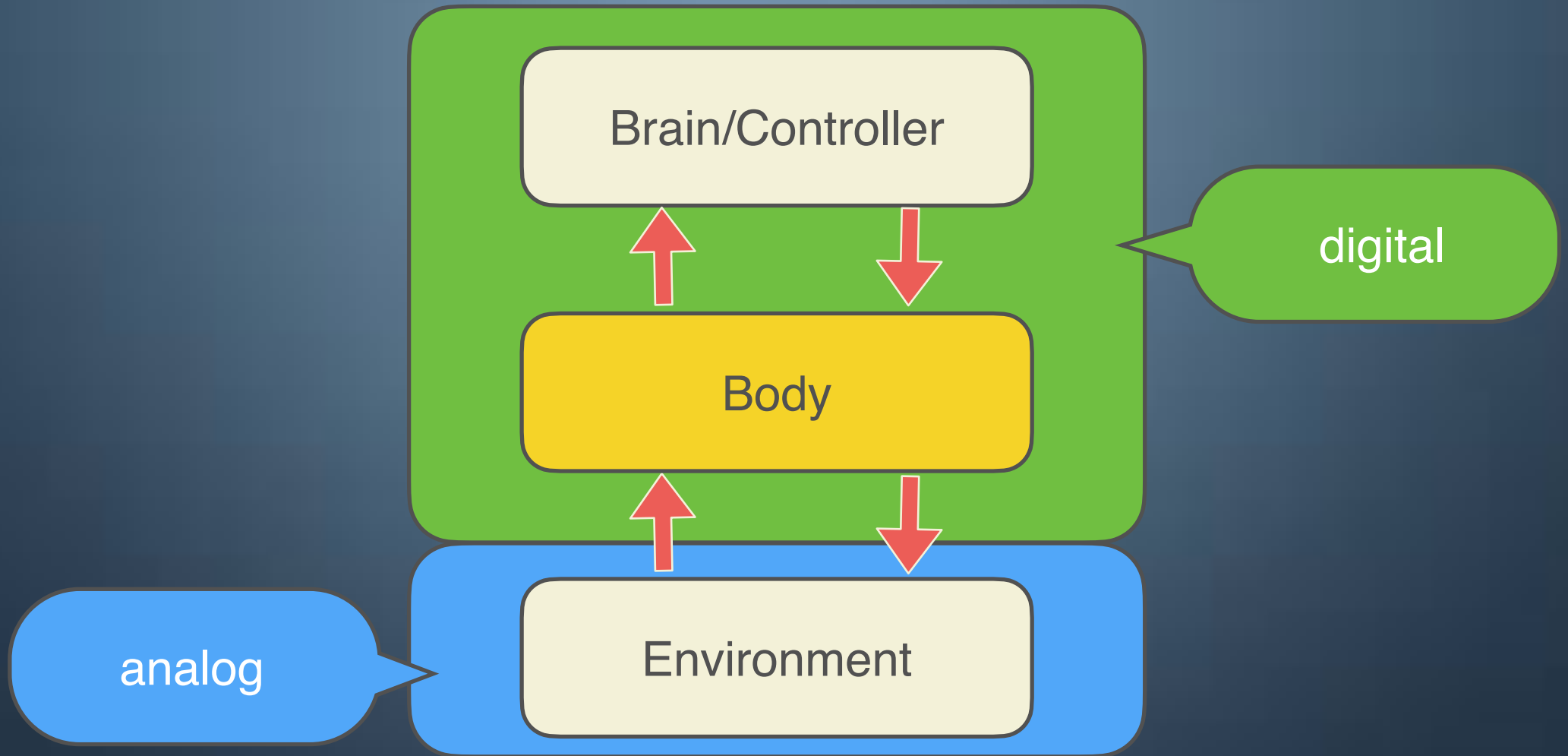


# MORPHOLOGICAL COMPUTATION

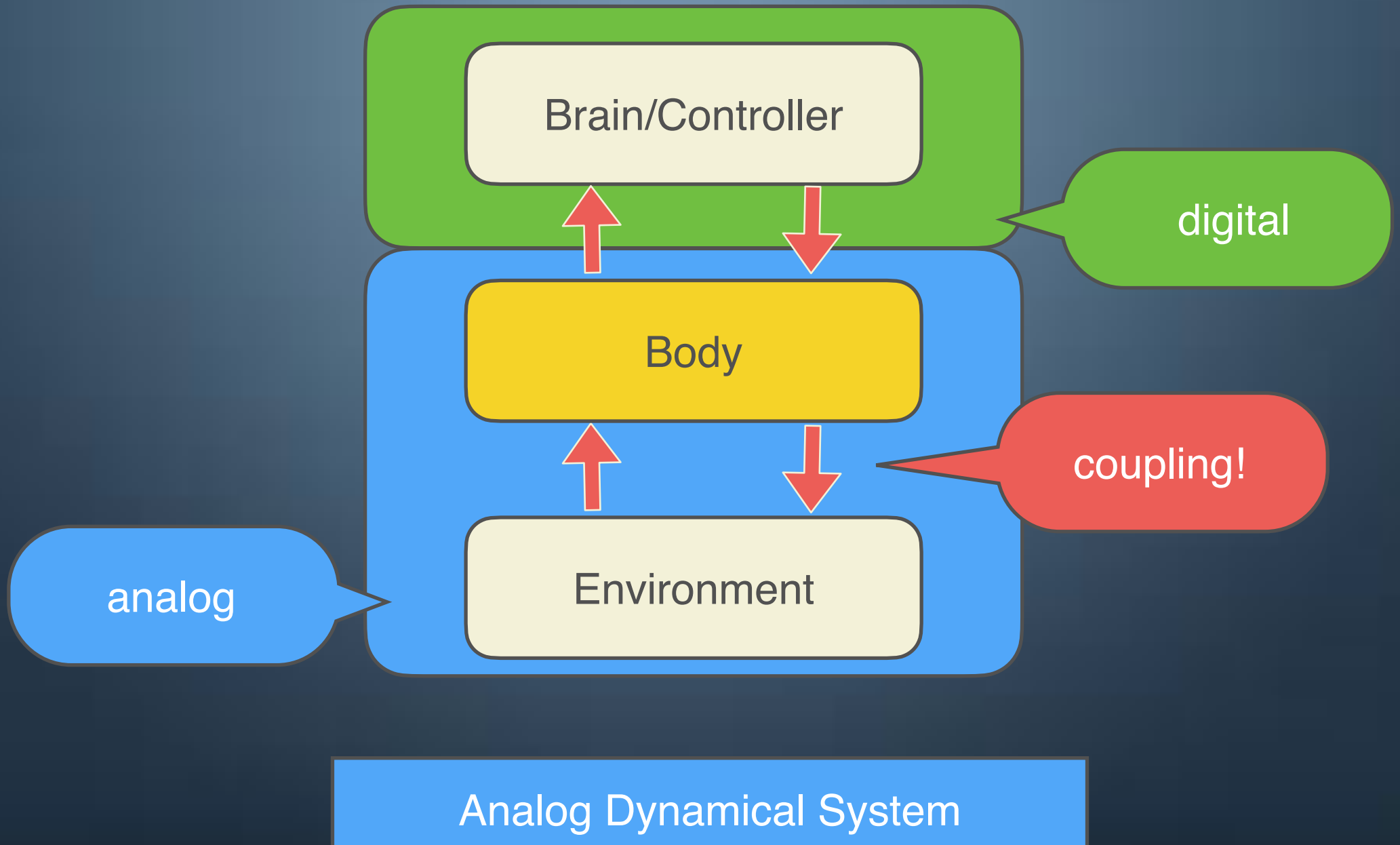


**What's the right framework?**

# STANDARD COMPUTATION / CONTROL APPROACH



# MORPHOLOGICAL COMPUTATION



# SOME IDEAS FOR DISCUSSION

Morphology = Analog Dynamical System

Control = Analog Dynamical System

Computation = Analog Dynamical System

Sensing = Analog Dynamical System

Growth = Analog Dynamical System

Learning = Analog Dynamical System

# SOME IDEAS FOR DISCUSSION

Analog dynamical system approach **is natural**

Analog dynamical system approach **is more inclusive**

Analog dynamical system approach **opens possibilities**

# GET IN TOUCH



@morphcomp

<https://www.morphologicalcomputation.org>



helmut.hauser@bristol.ac.uk

## MORE INFORMATION

theory

Hauser, H. et al. "Towards a theoretical foundation for morphological computation with compliant bodies"  
Biological Cybernetics, Springer Berlin / Heidelberg, (2011), 105, 355-370  
<https://link.springer.com/article/10.1007/s00422-012-0471-0>

theory

Hauser, H. et al. "The role of feedback in morphological computation with compliant bodies"  
Biological Cybernetics, Springer Berlin / Heidelberg, (2012), 106, 595-613  
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intro

Hauser, H.; Fuchslin, R.M.; Nakajima, K. "Morphological Computation – The Physical Body as a Computational Resource"  
Opinions and Outlooks on Morphological Computation, editors Hauser, H.; Fuchslin, R.M. and Pfeifer, R., Chapter 20, pp 226-244, 2014,  
ISBN 978-3-033-04515-6 [https://www.dropbox.com/s/zg79mw35nvq4bba/Chapter\\_20\\_Hauser.pdf?dl=0](https://www.dropbox.com/s/zg79mw35nvq4bba/Chapter_20_Hauser.pdf?dl=0)

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Nakajima, K., Hauser, H., Li, T. & Pfeifer, R. "Information processing via physical soft body" Scientific Reports. 5, 10487 (2015)

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Judd, E., Digumarti, K. M., Rossiter, J. & Hauser, H. NeatSkin: A Discrete Impedance Tomography Skin Sensor. RoboSoft (2020)

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Judd, E., Soter, G., Rossiter, J. & Hauser, H. Sensing through the body - Non-contact object localisation using morphological computation. in RoboSoft, (2019)

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many others in real robots in sensing, actuation, learning and control – contact me if you want more information