1 Parameter Plots

The following plots compare the quadruped inverse parameters found by independent and joint inverse optimization for all of the parameters listed in table 1.

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Figure 1: From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for an ostrich.

Figure 2: From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for a Thomson’s gazelle.

Figure 3: From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for an elephant.
Figure 4: From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for a giraffe.