Supplemental Material for
Generalizing Locomotion Style to New Animals With Inverse Optimal Regression

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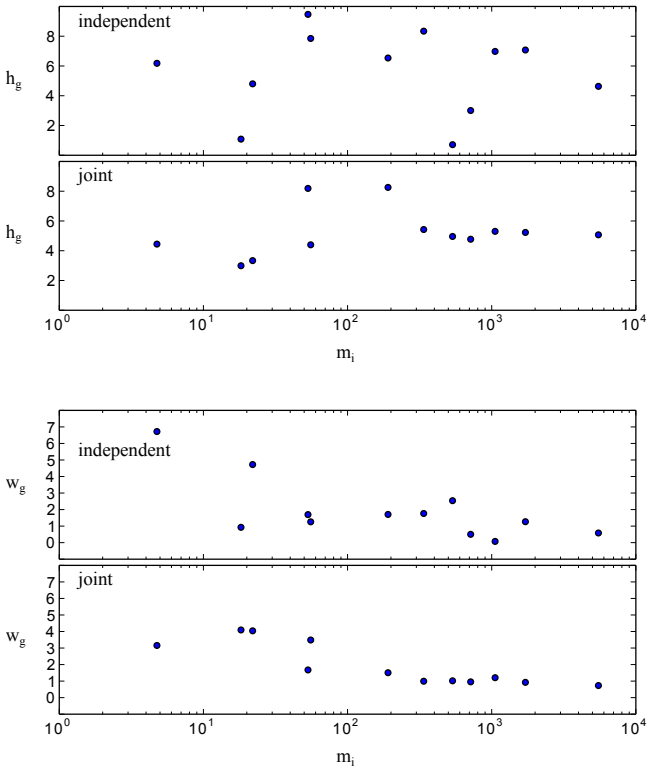
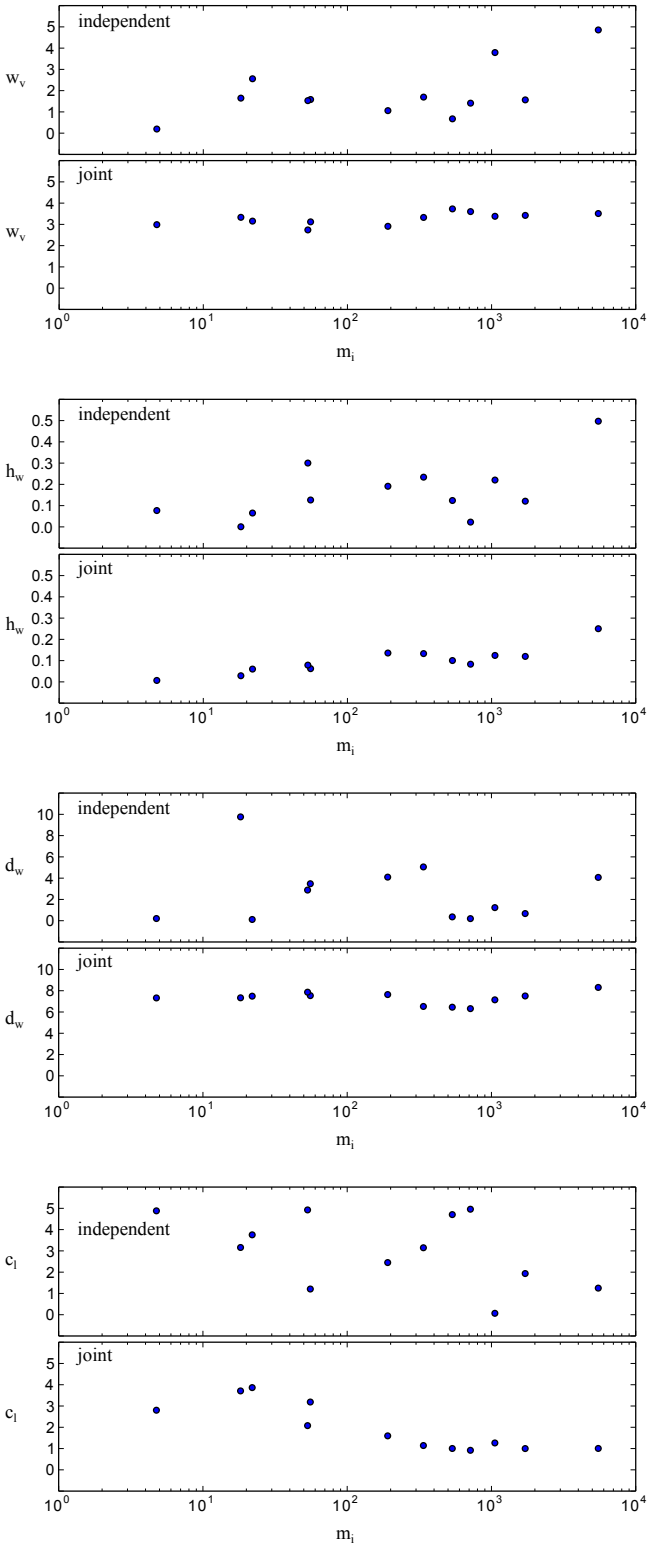
Adobe Research

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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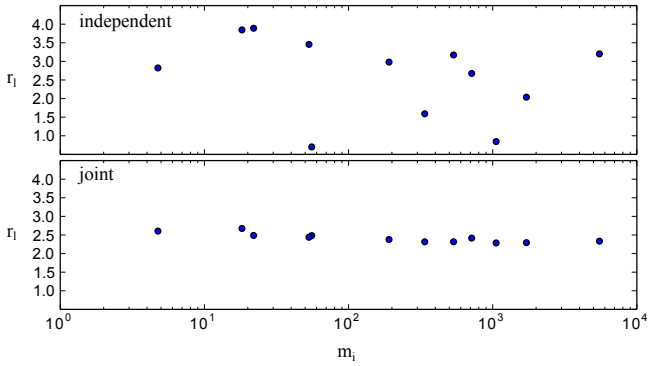
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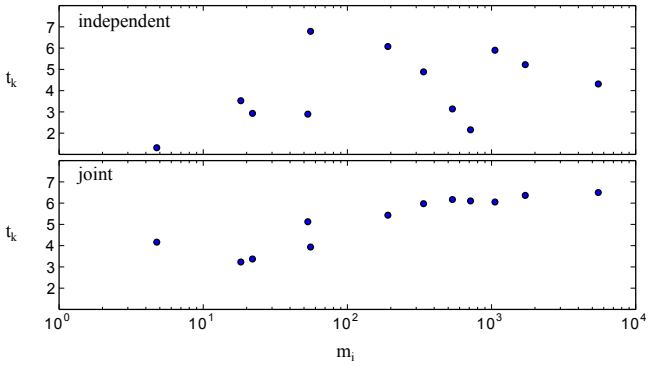
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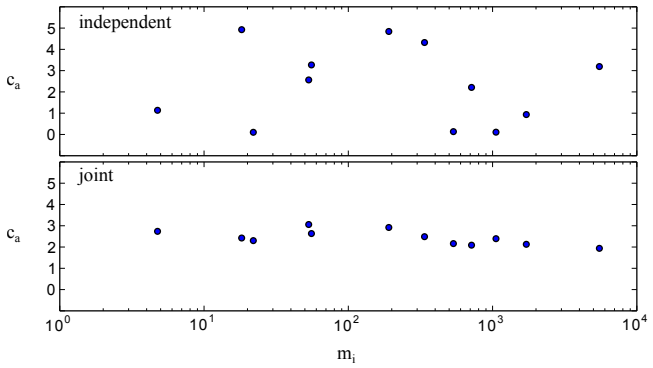
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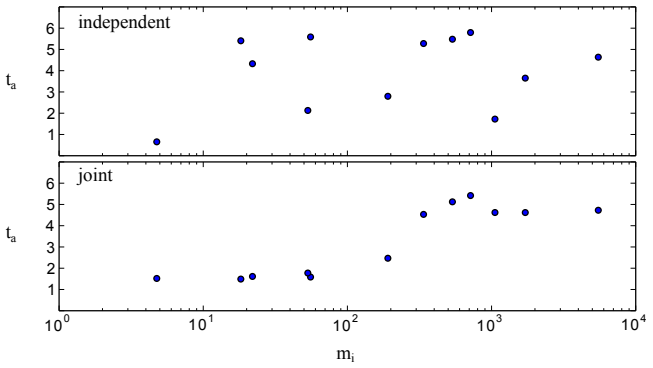
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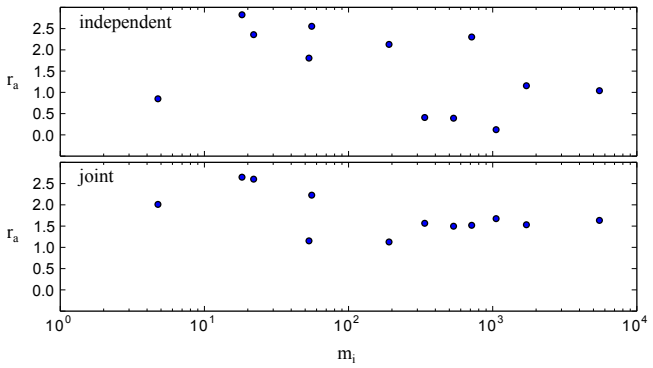
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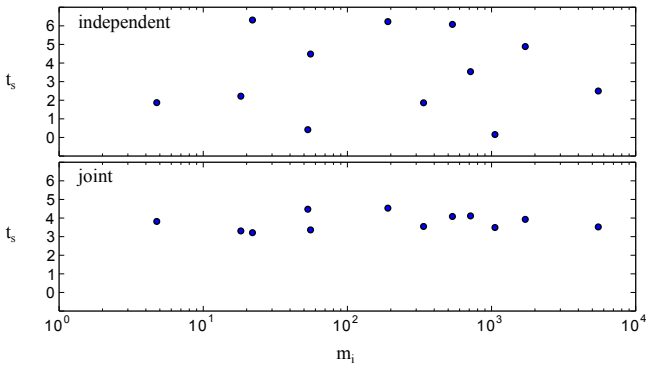
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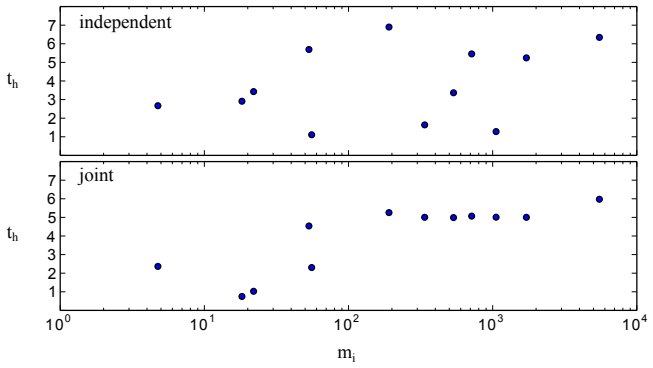
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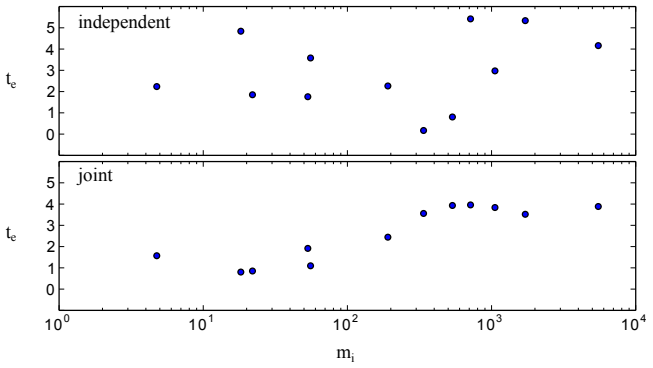
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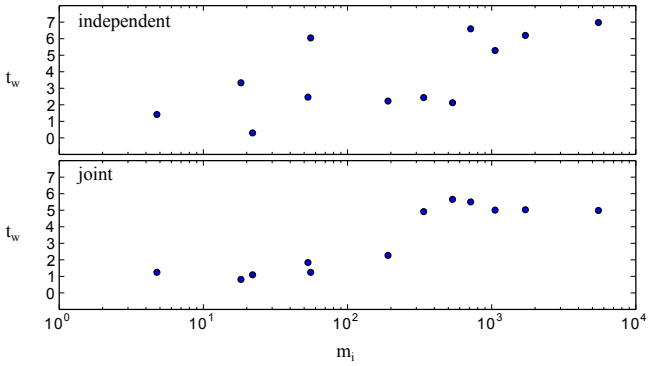
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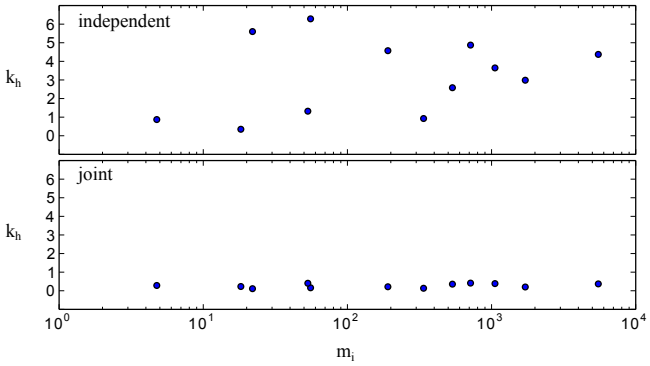
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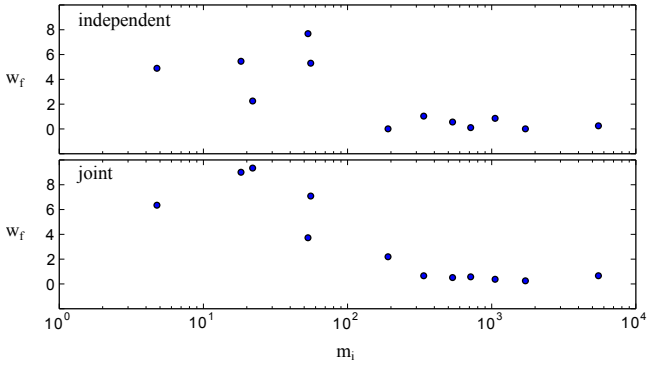
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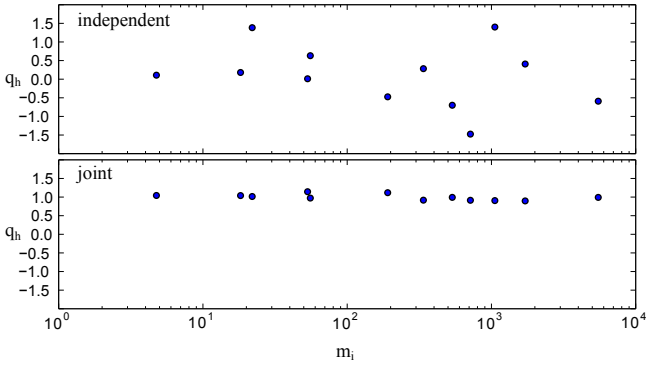
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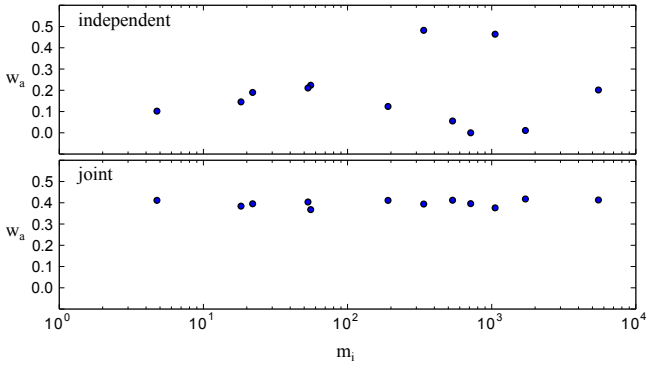
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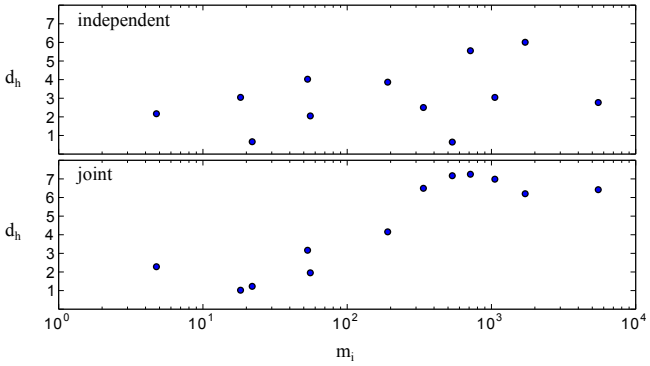
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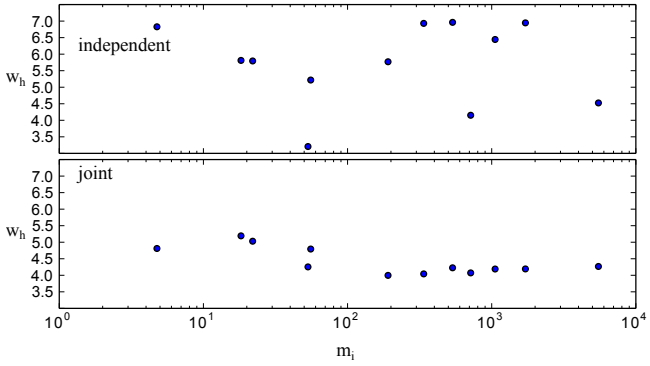
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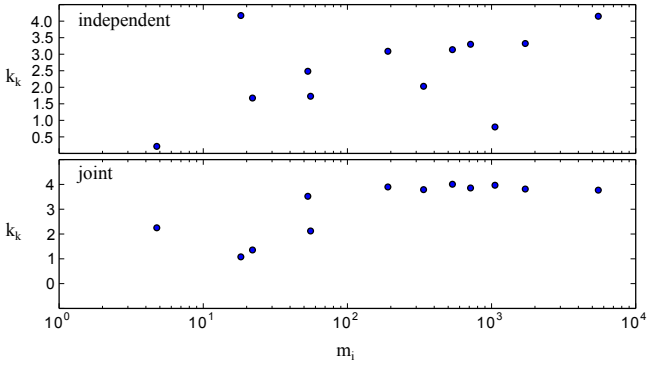
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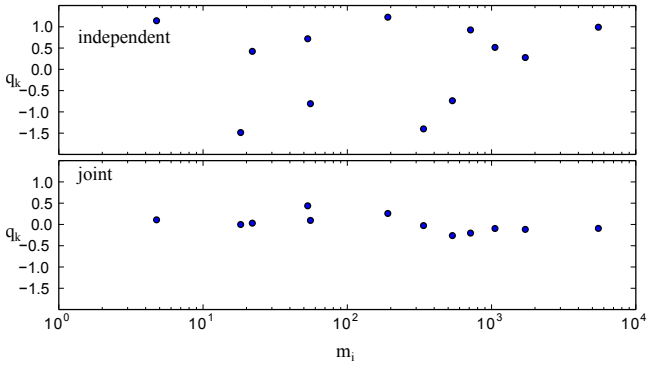
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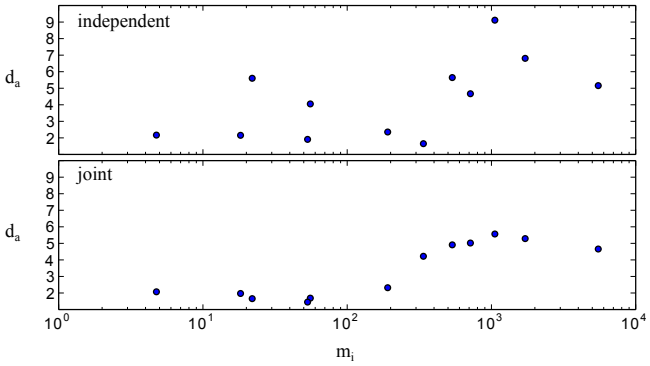
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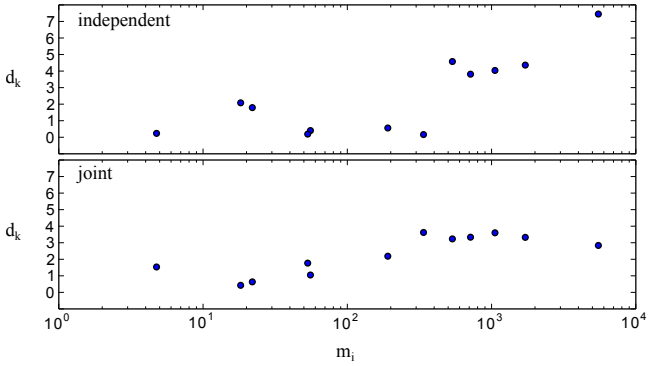
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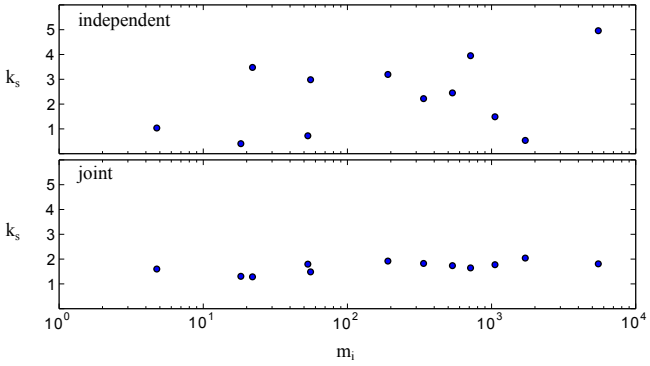
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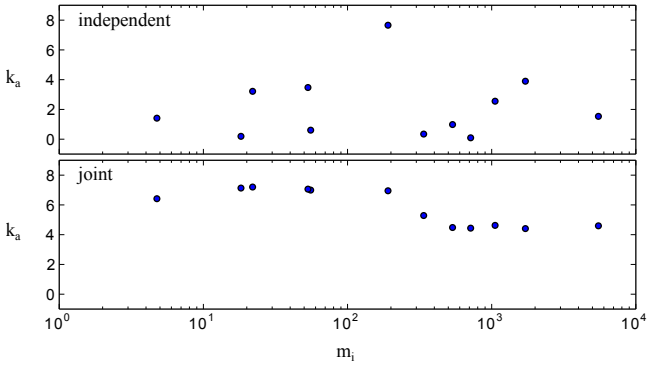
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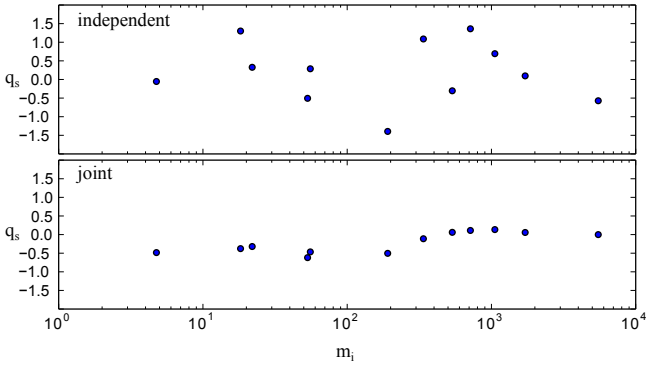
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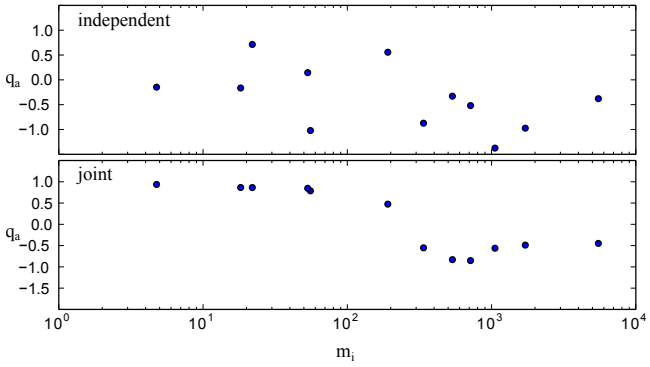
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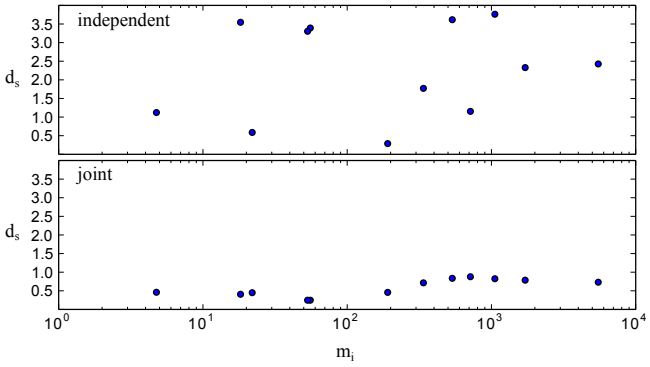
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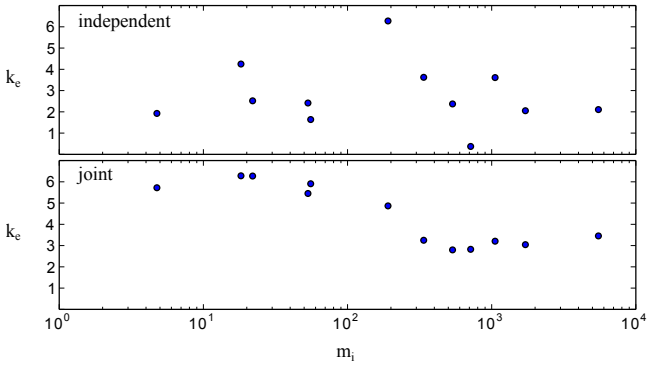
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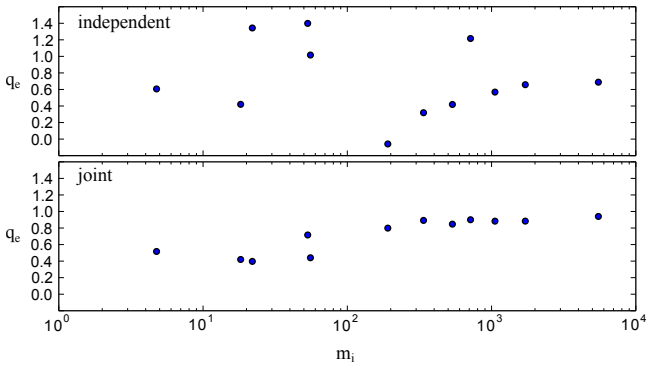
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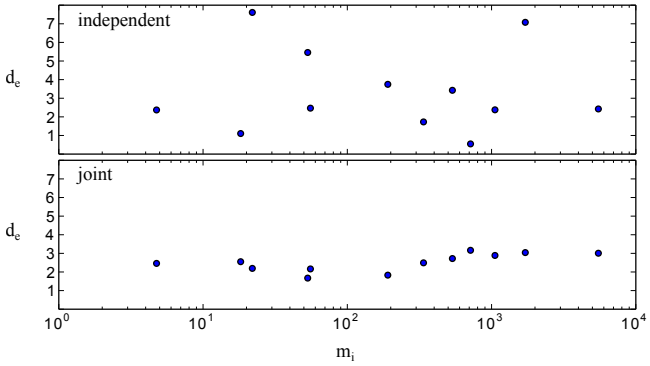
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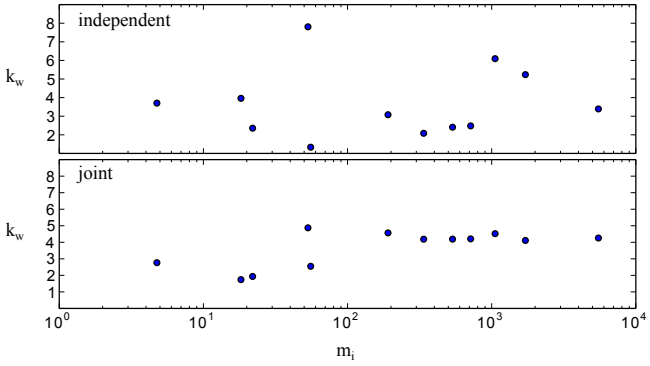
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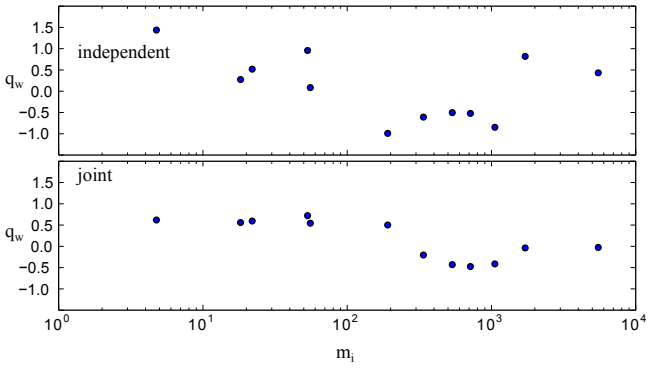
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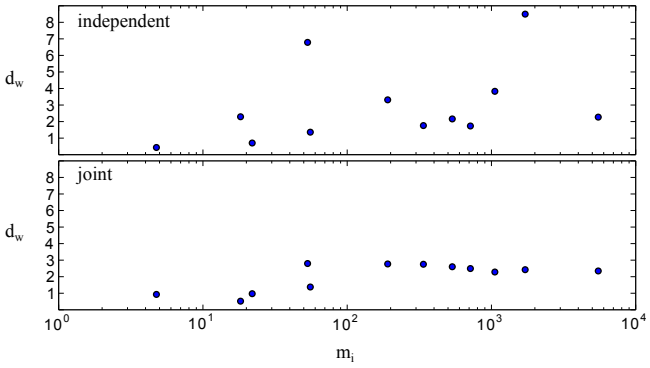
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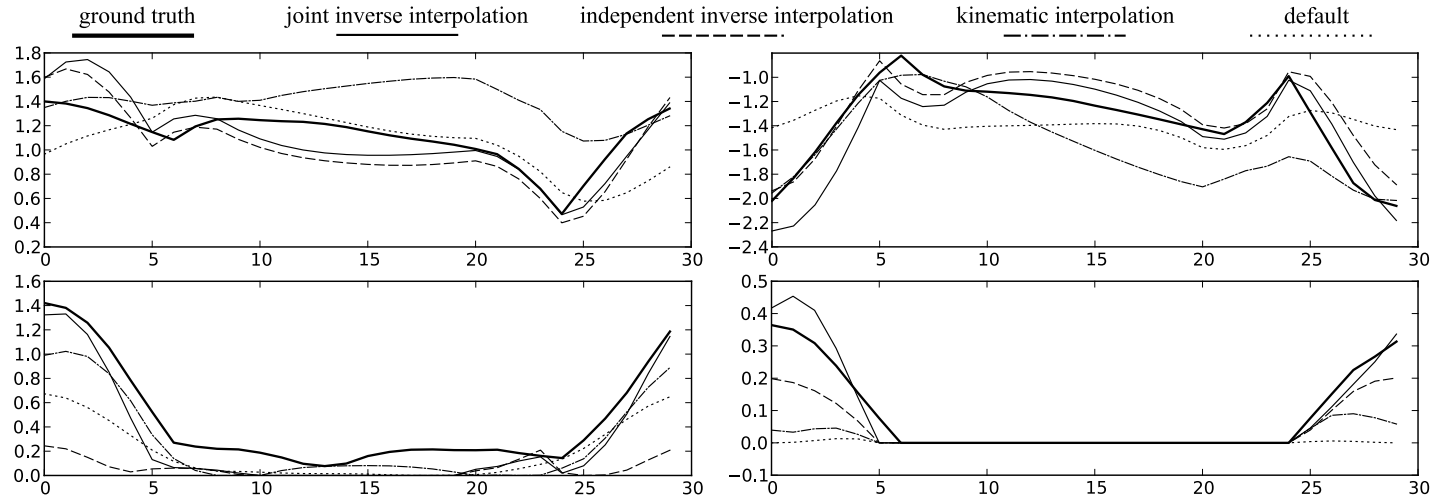

Figure 1: *From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for an ostrich.*

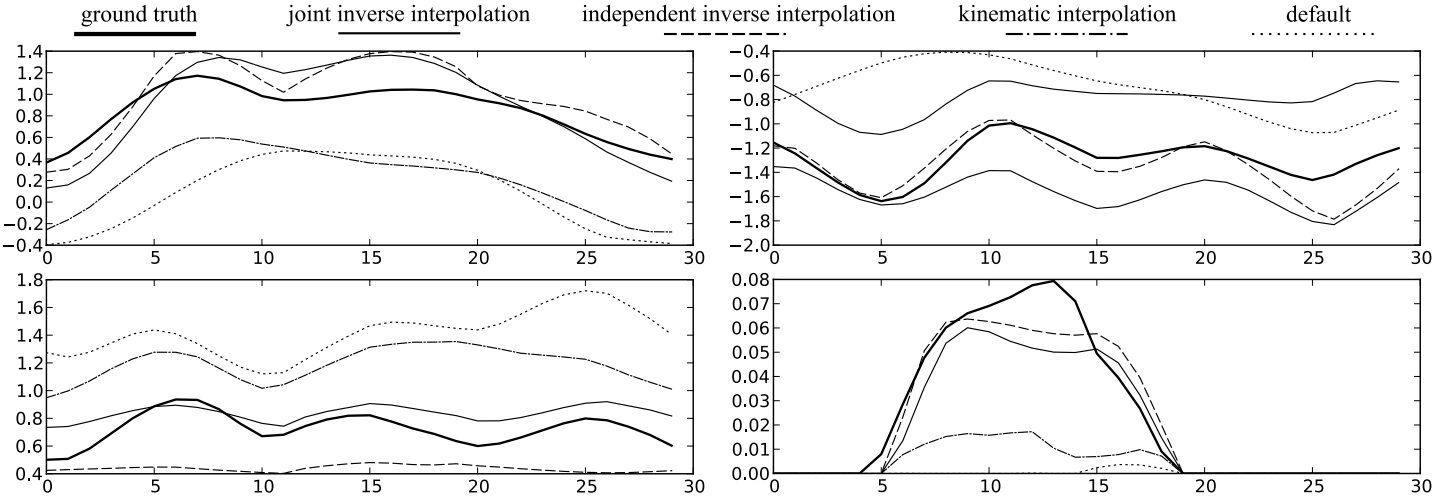

Figure 2: *From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for a Thomson's gazelle.*

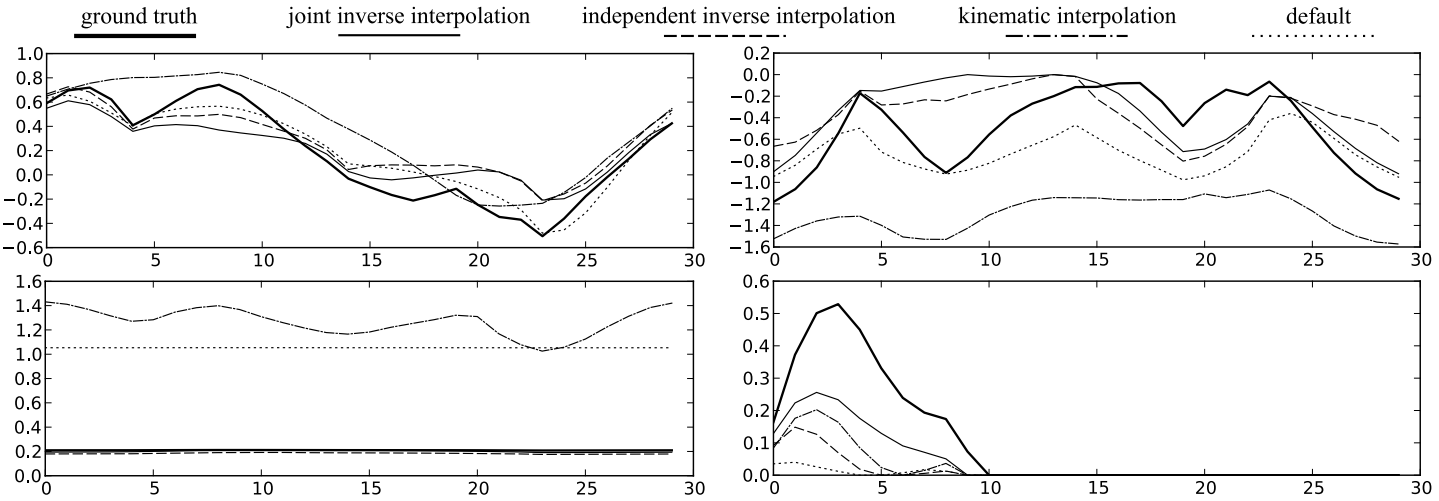

Figure 3: *From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for an elephant.*

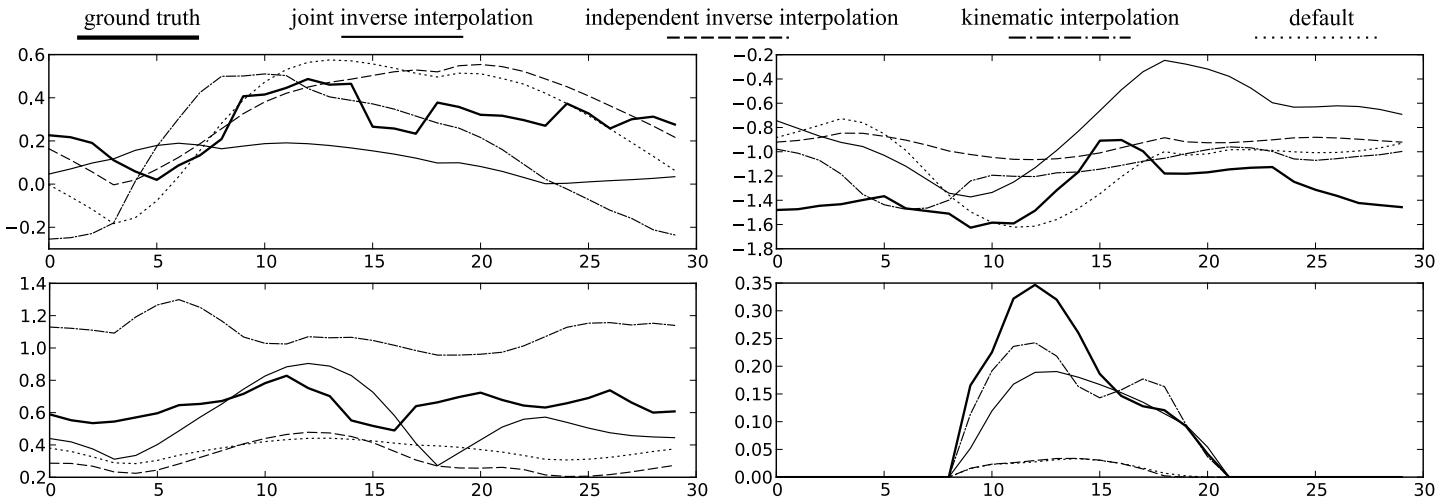

Figure 4: *From top left to bottom right: plots of the hip angle, knee angle, ankle angle, and foot height over the frames in gaits for a giraffe.*