

Neurons and Robots

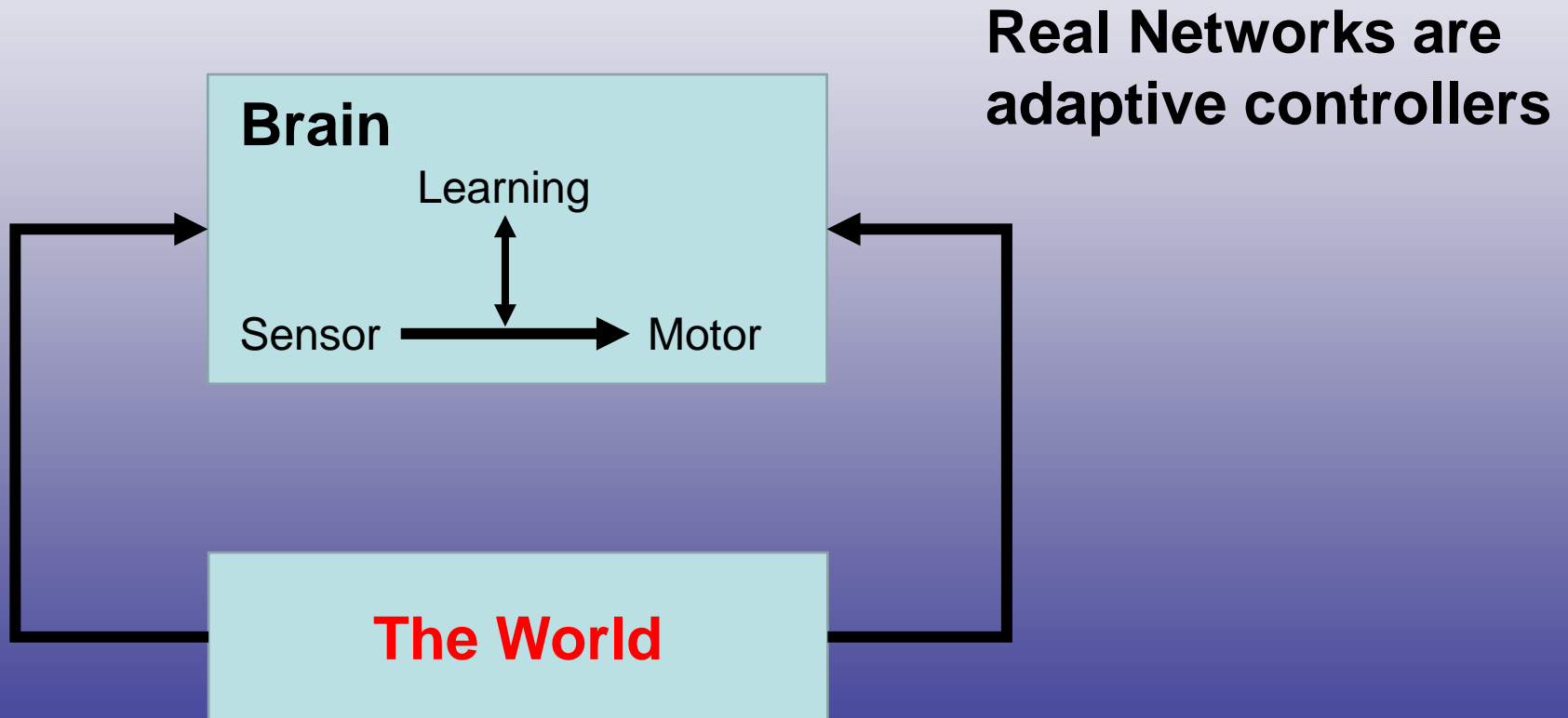
Using Networks for Control and Learning to Behave

Old Man of Storr (Isle of Skye)

F. Wörgötter
Bernstein Center for Comp. Neurosci.
Göttingen

The great divide:

„Neural“ Networks are (still) no neural networks.

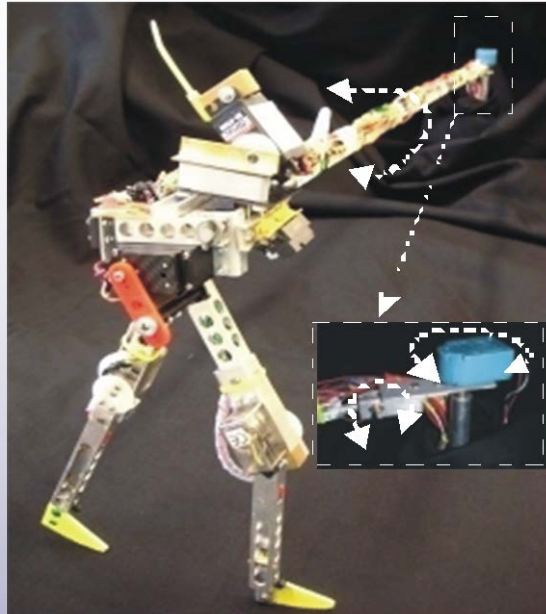


Networks and Control

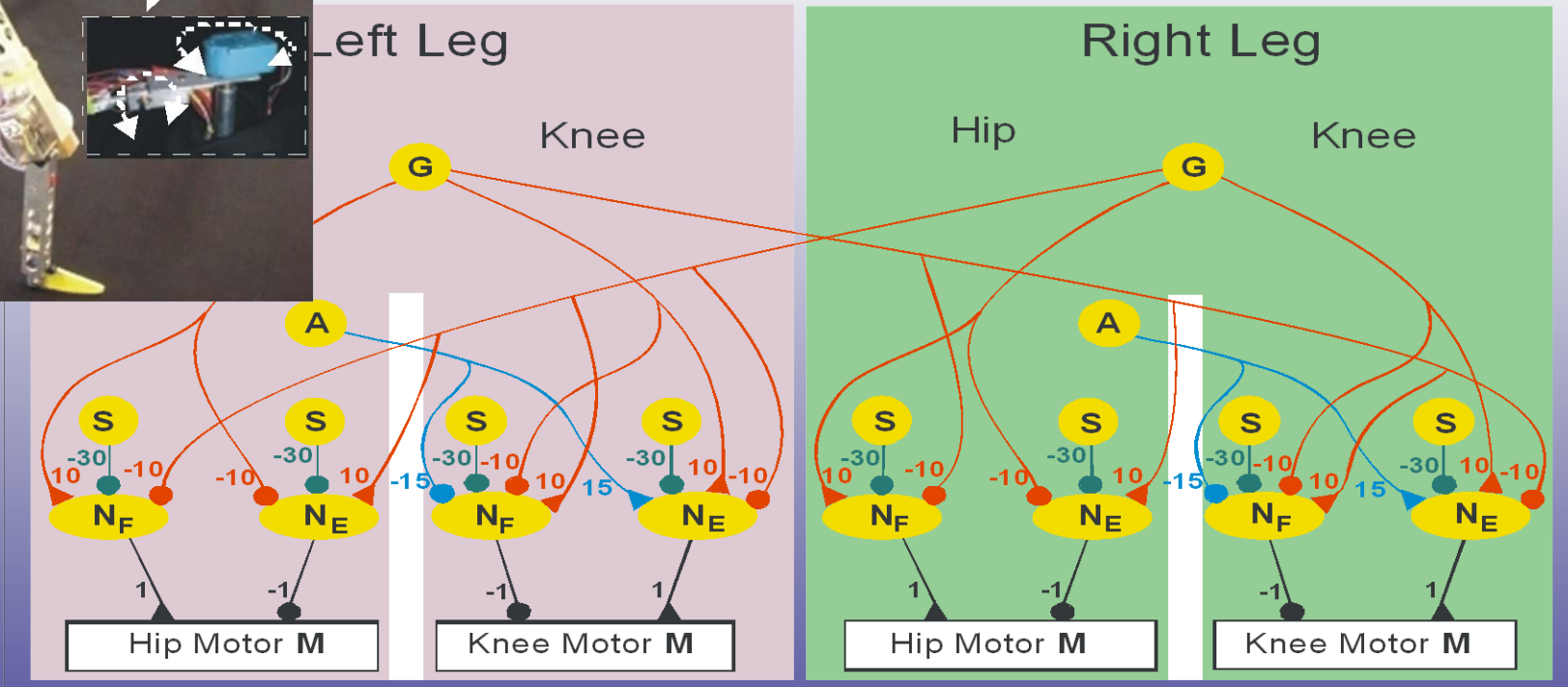
- Reflex based neural control – RunBot (2007)
 - Learning to avoid a reflex
- AMOS W6, a six-legged robot (2010)
 - Deterministic Chaos and its control
 - Demonstration of a large behavioral repertoire
- Learning Goal directed manipulation actions (2015)
 - Memory in behaving networks

RunBot, the Reflex Machine

PLoS CB, 2007



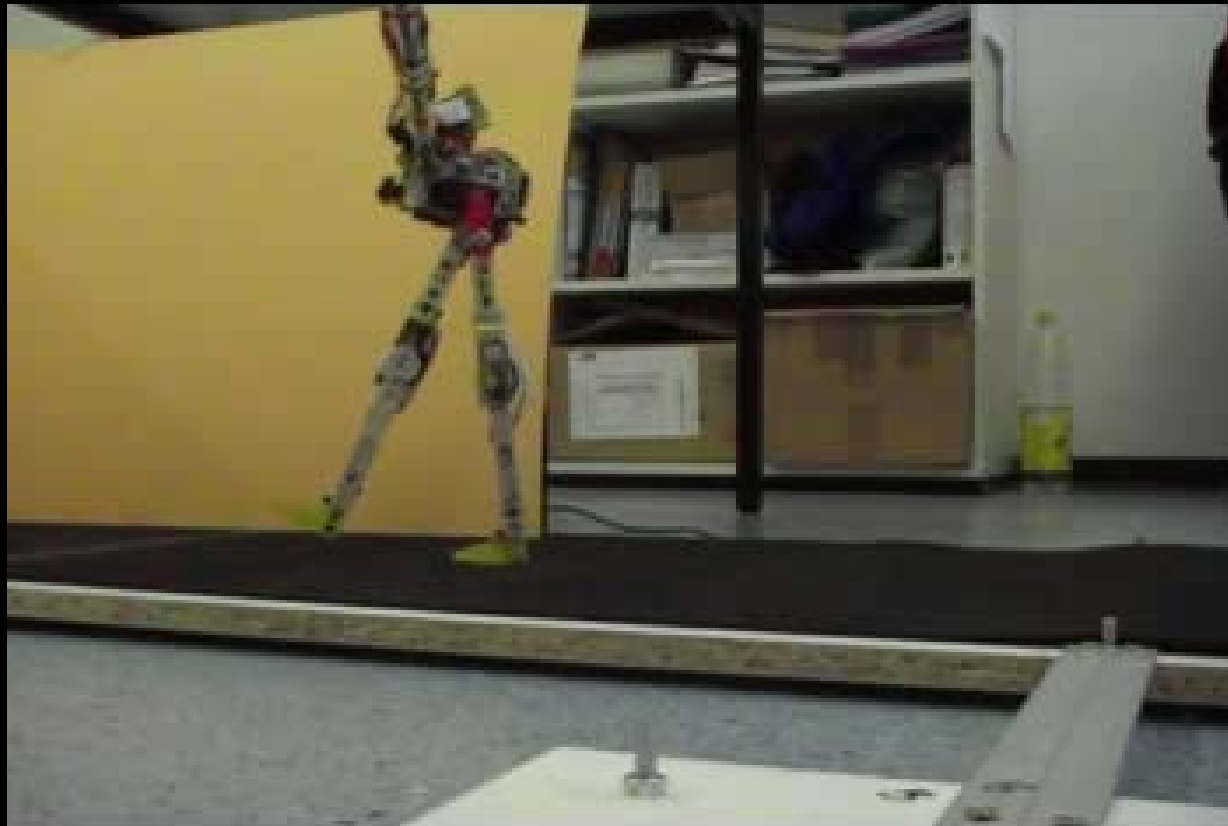
Leg Control



Motor neuron
 Sensor neuron/receptor
 Excitatory synapse
 Inhibitory synapse

15 Sensors, 5 DOF (constrained), 19 neurons

RunBot: Learning to walk up a slope



BBC, July 07

Mumbai Mirror July 07

New York Times July 07

AAAS Sci Update July 07

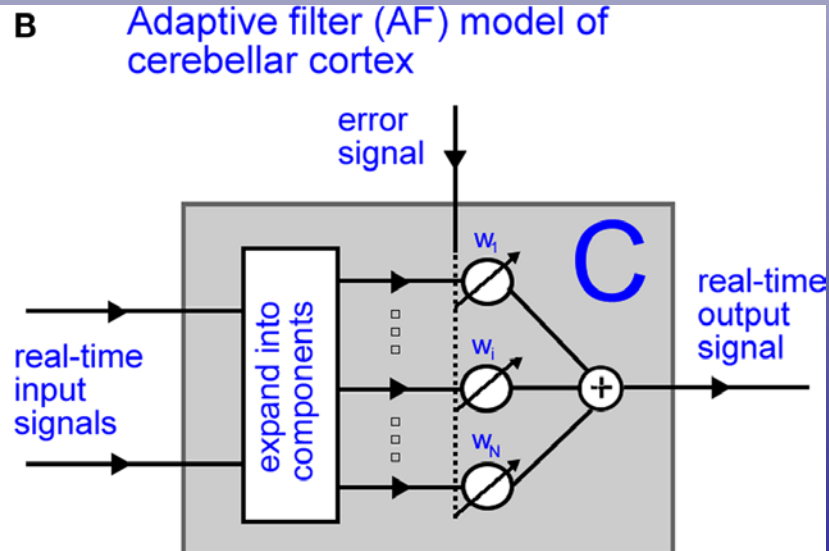
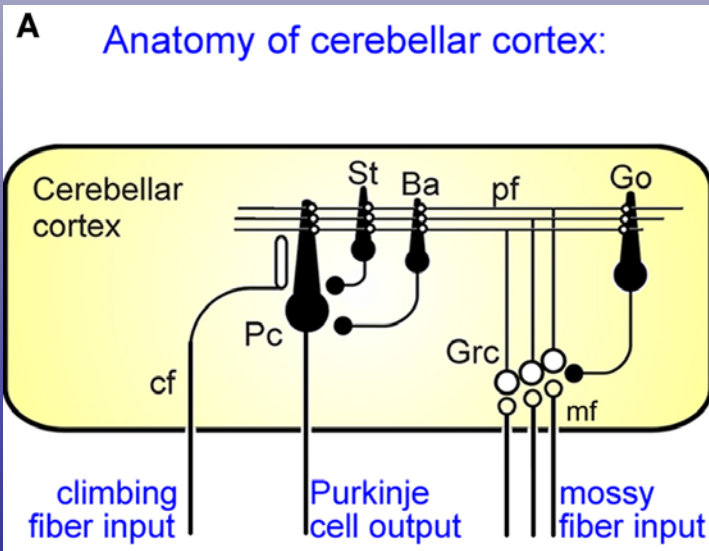
What happens here?

Cerebellar Reflex Avoidance Learning (abstracted)

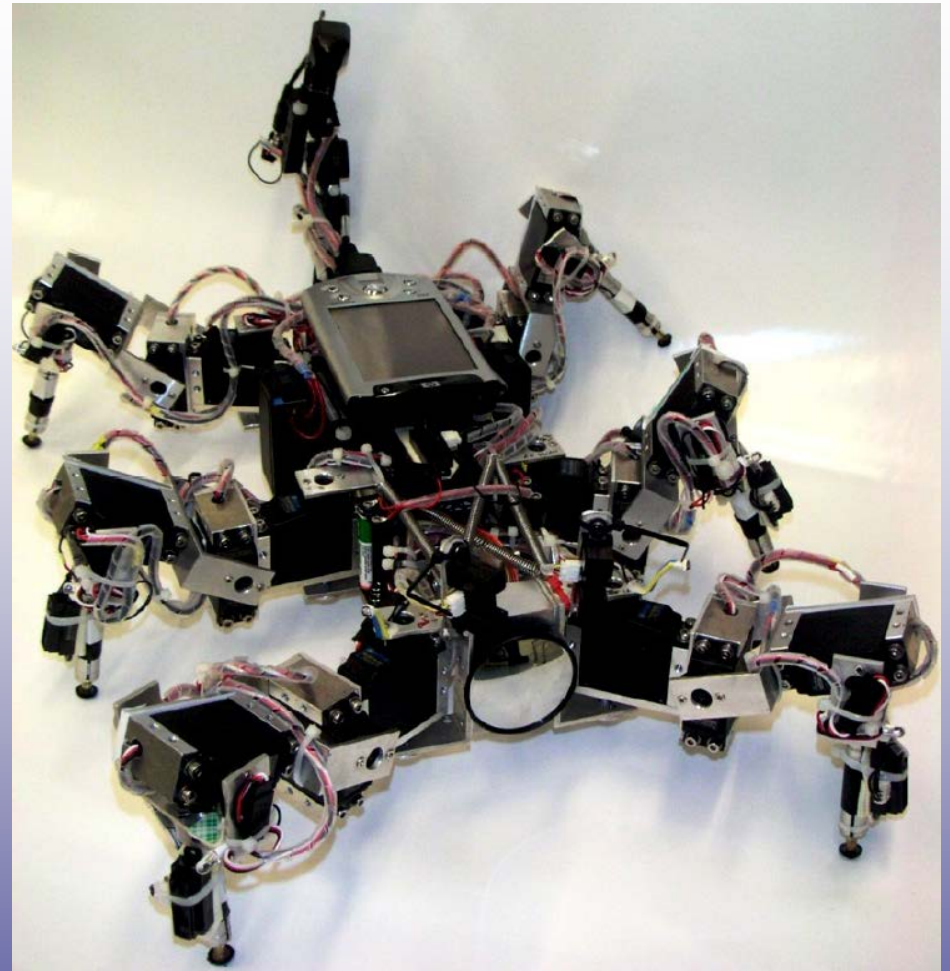
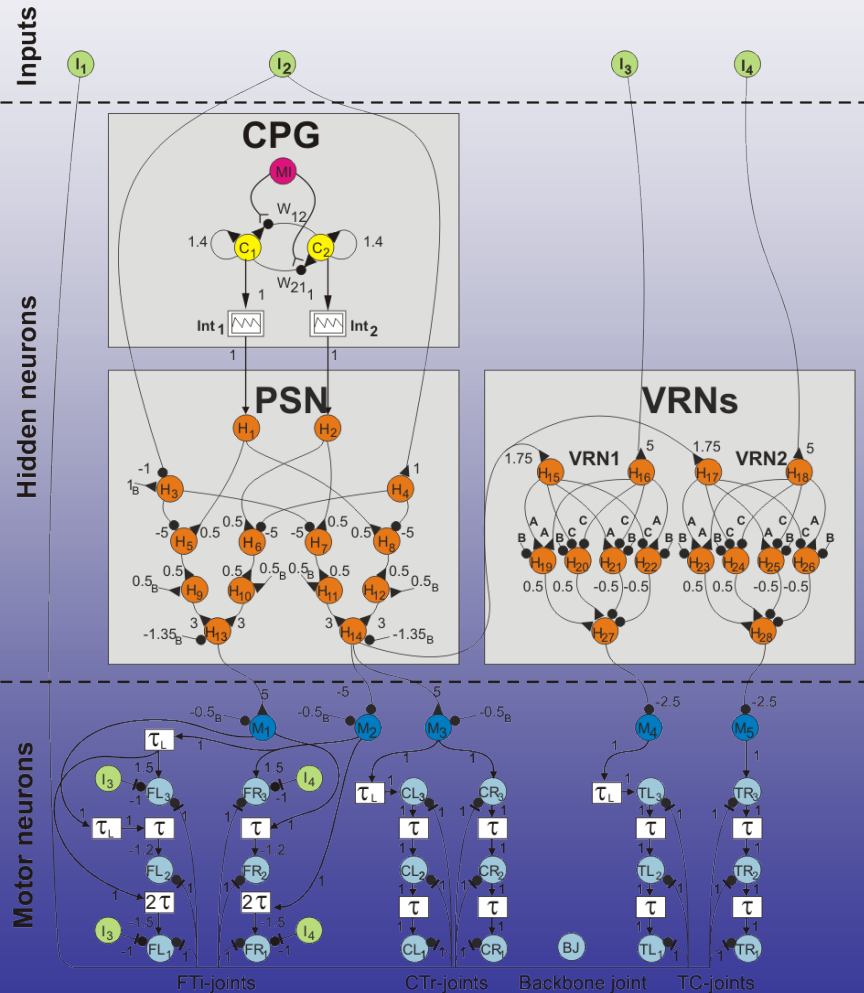
Look → Move

instead of

Ouch → Move

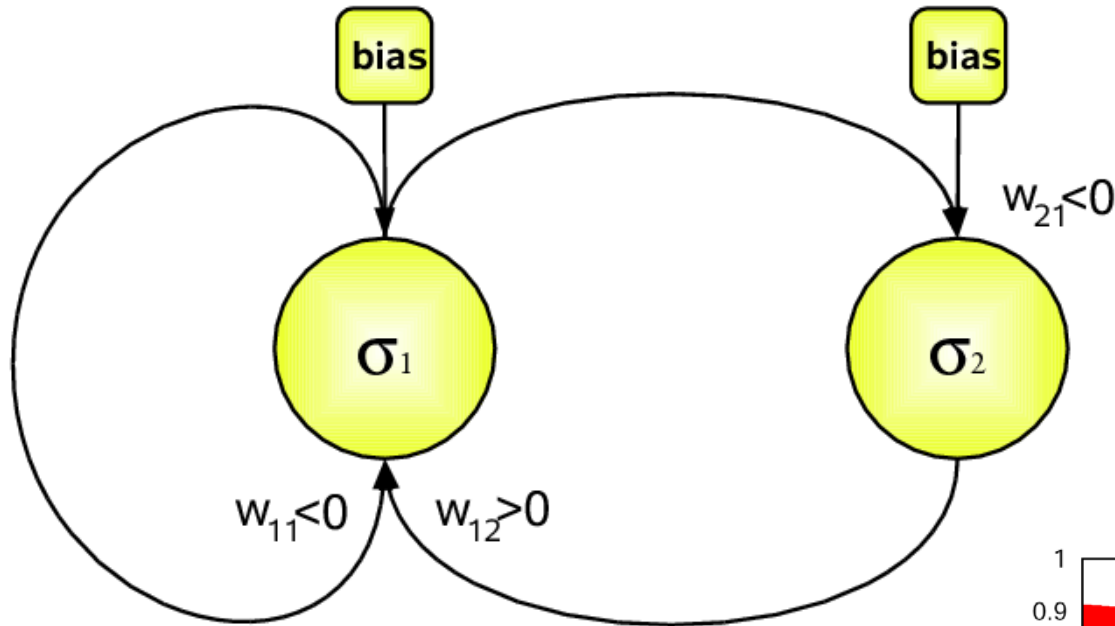


How to control Chaos in networks

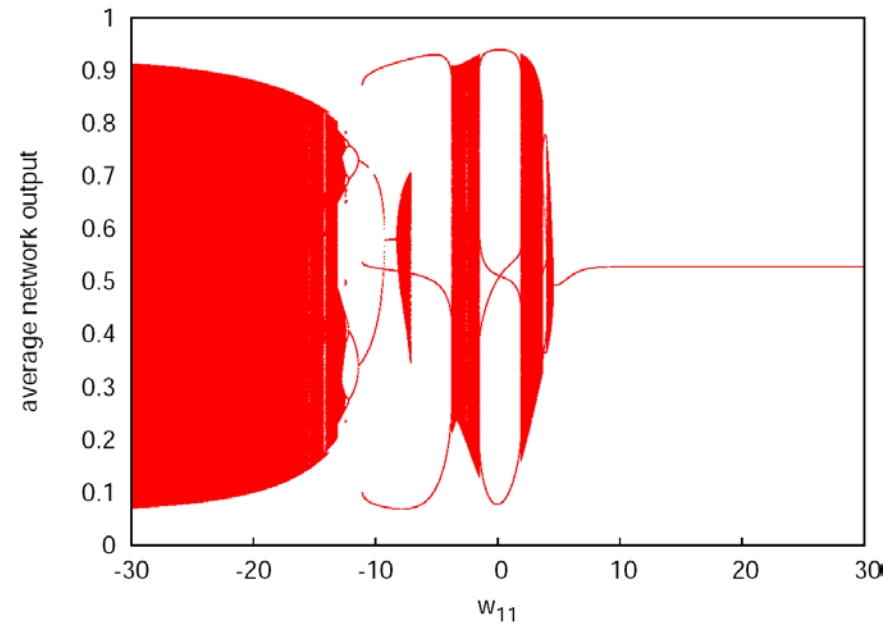


**>30 Sensors, 19 DOF
71 neurons**

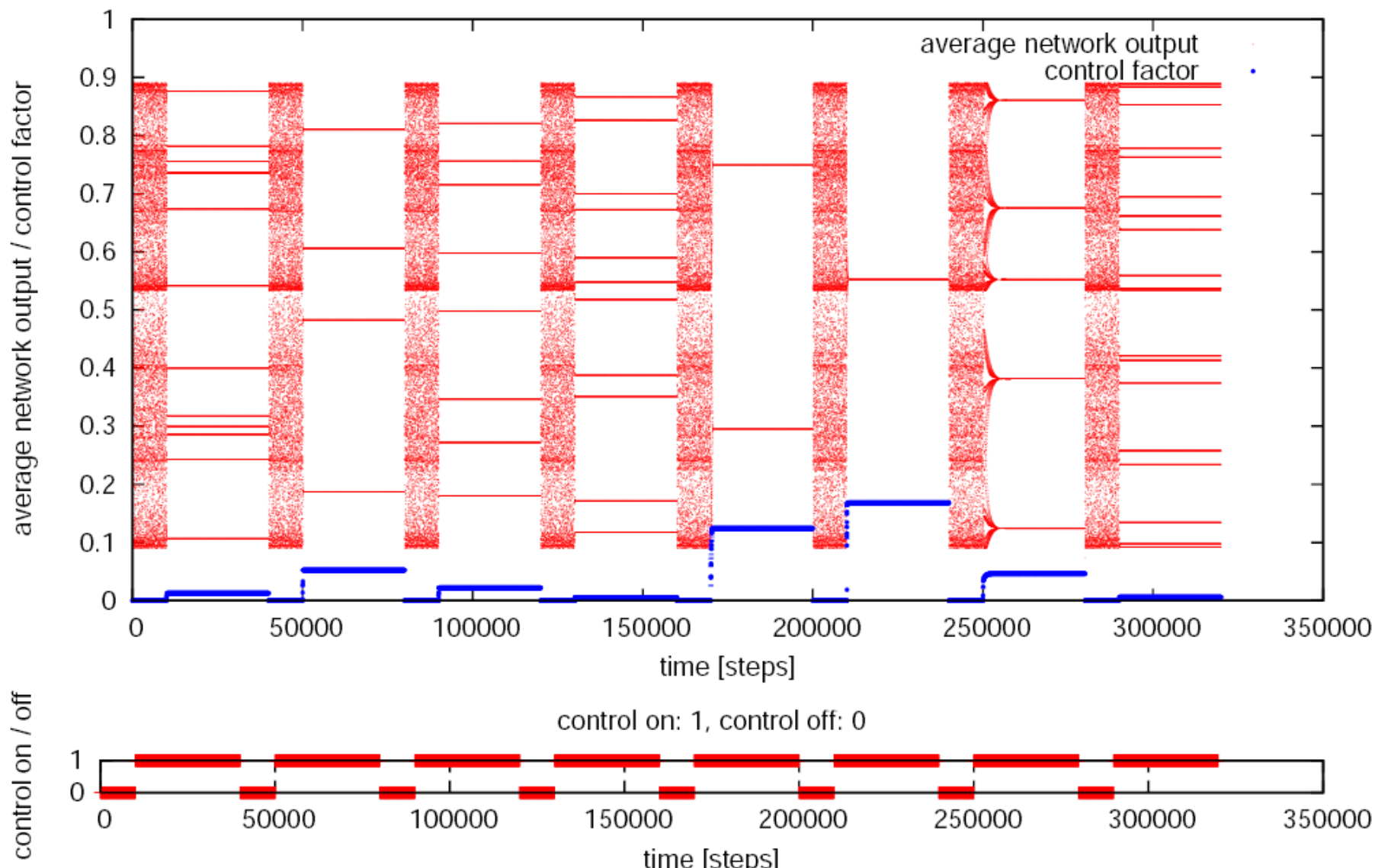
Two neurons suffice to create a large behavioural repertoire

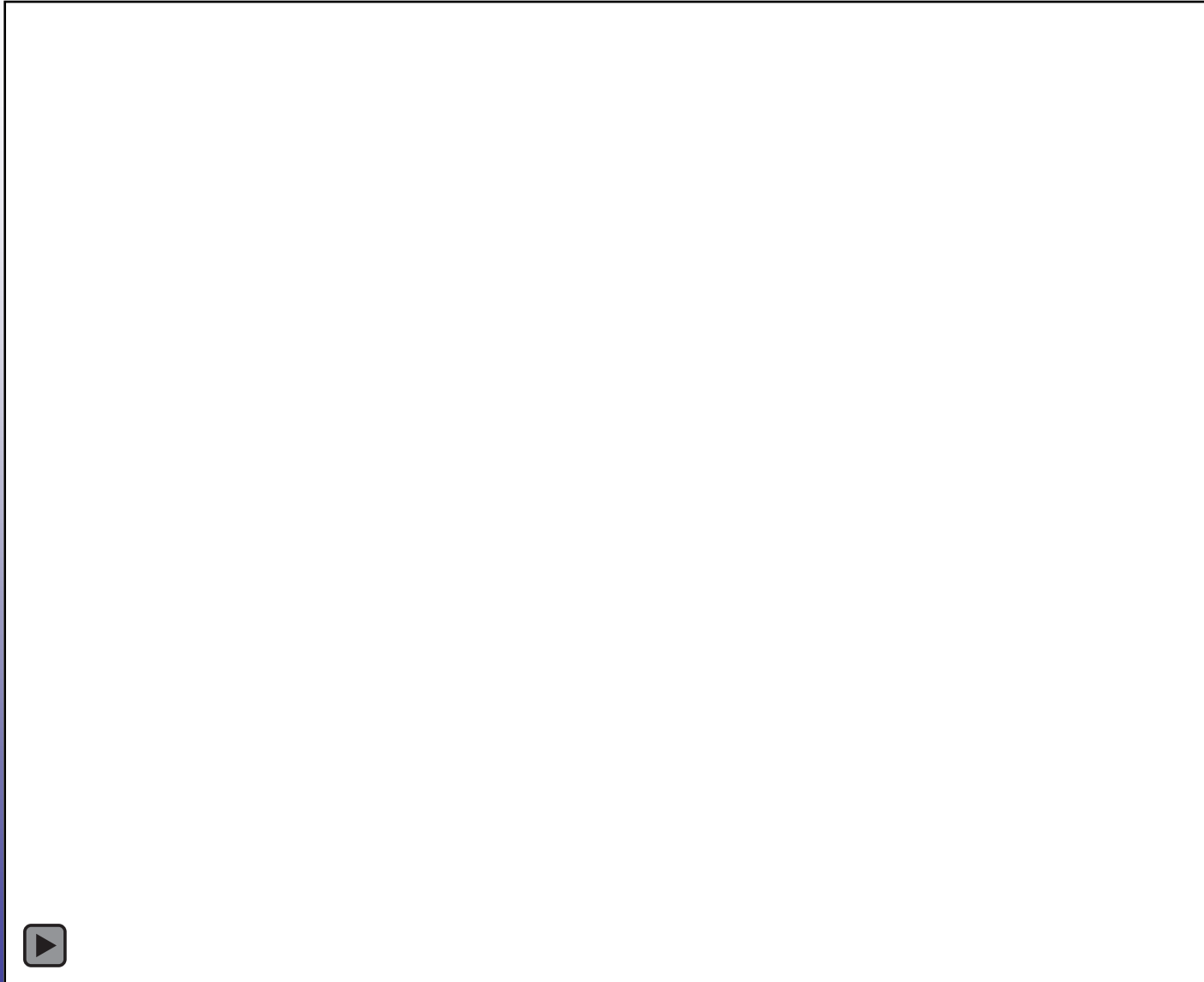


The bad news is:
these circuits almost
always produce
chaotic outputs
(Pasemann)



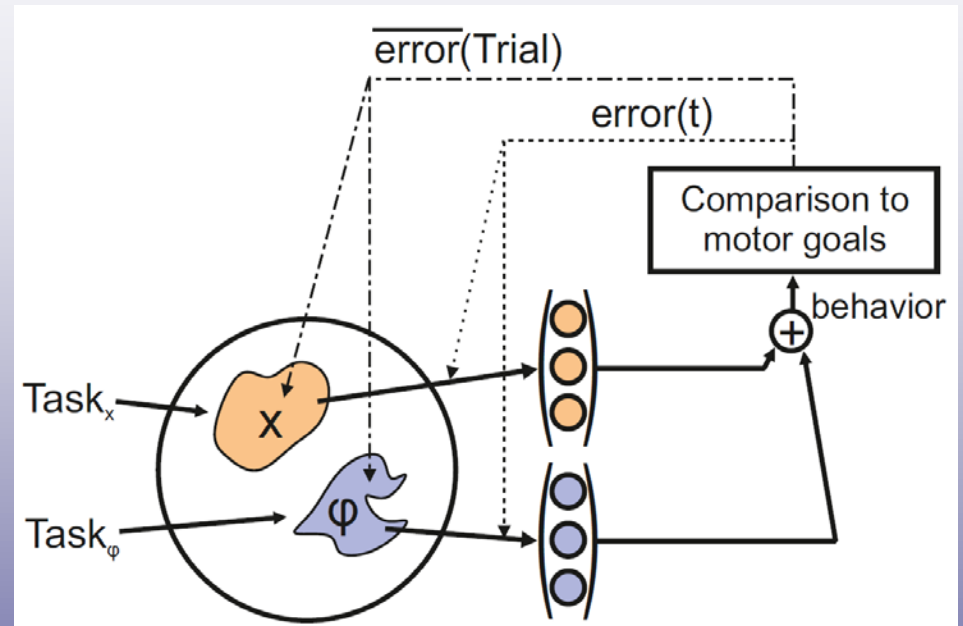
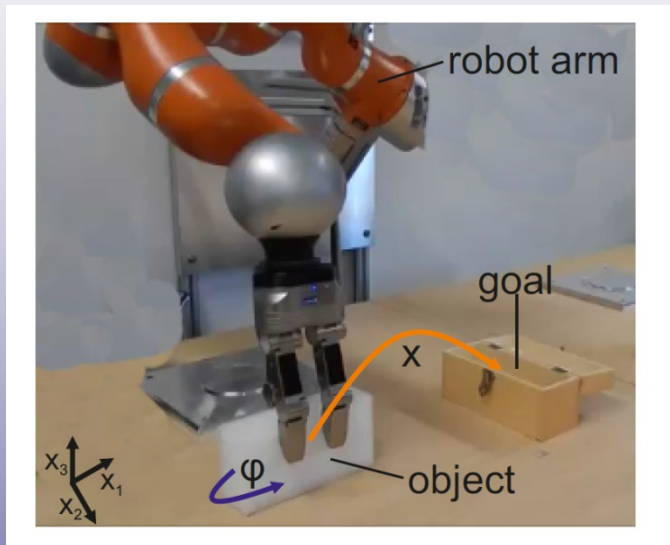
Chaos control can be used to create periodic outputs





Robot Arm Control

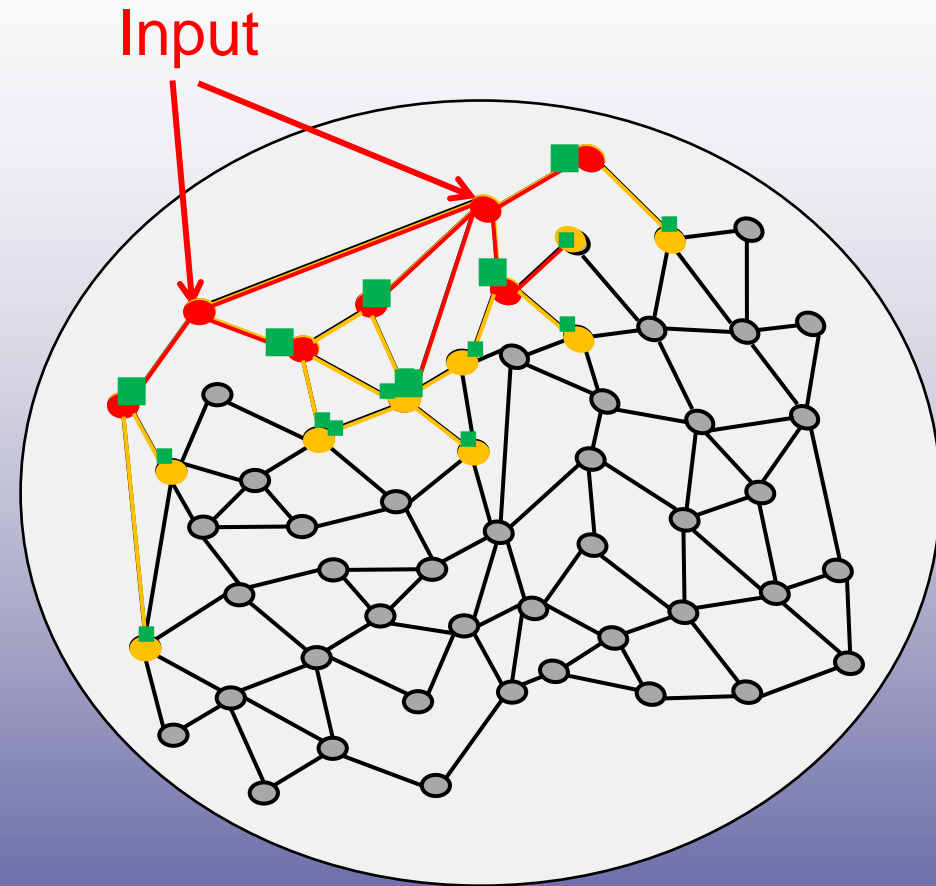
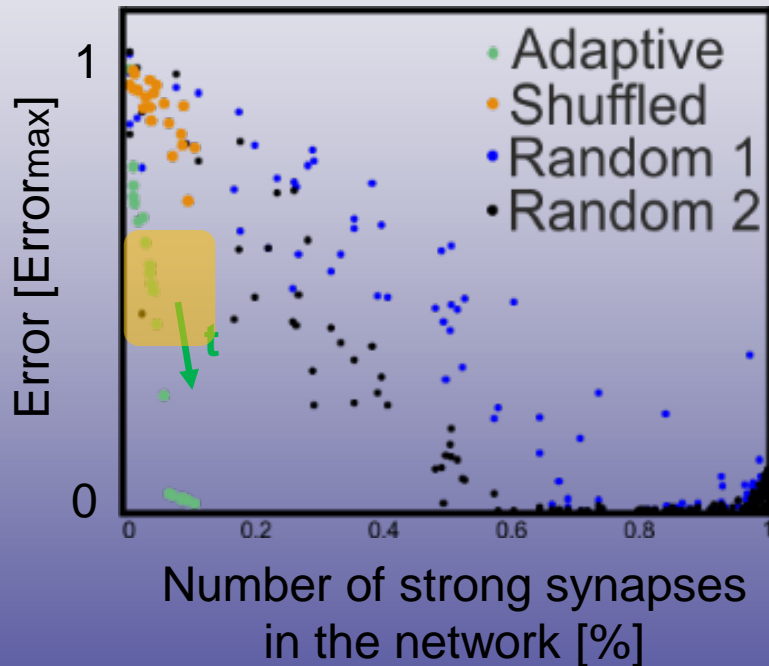
The self-organization of large networks



The robot has to learn to **rotate** and **translate** the object into the box. Thereby, both movements are learned **independently** from each other (alternating).

Camera as sensor, 7 DOF, >1000 neurons

Growing a behavior-control network

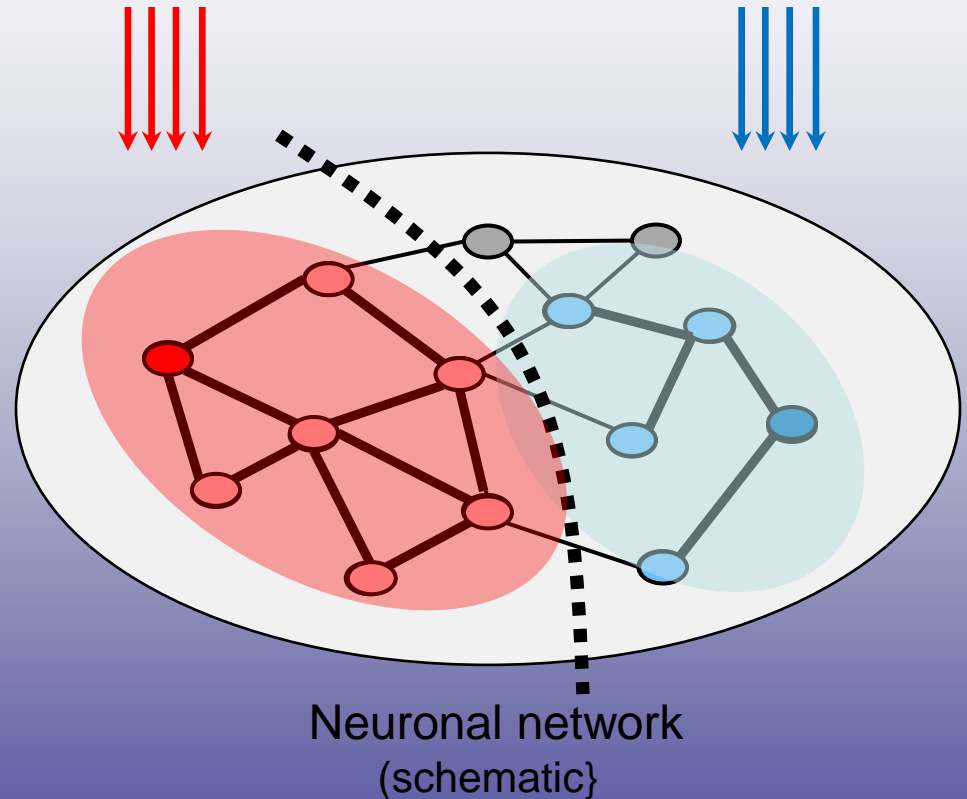


Neuronal network
(schematic)

Growing (non-static) Network

Self Organized Network Formation

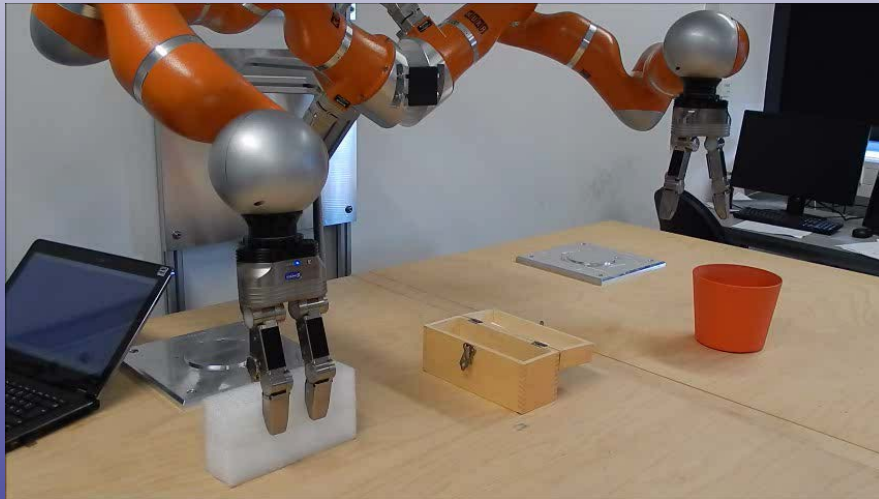
The combination of **Hebbian Learning** with **Synaptic Scaling** allows input driven **self-structuring** of large networks into **many small but powerful Reservoirs**.



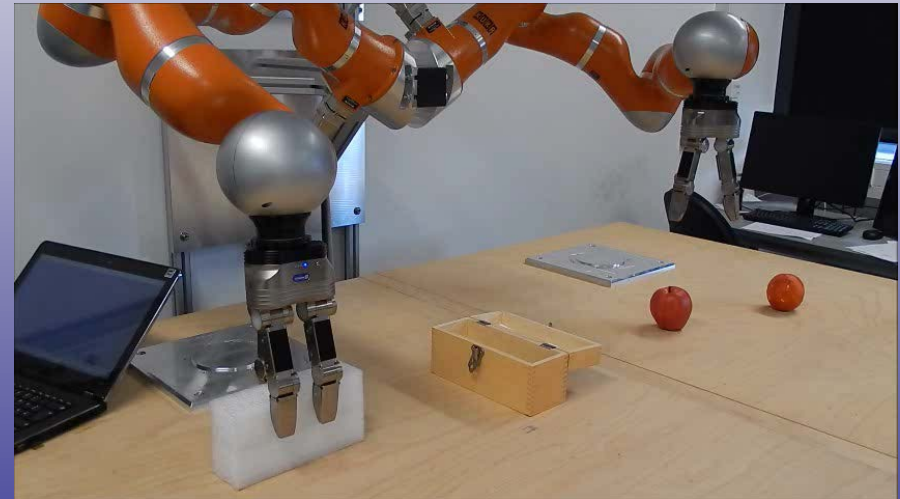
Growing (non-static) Network

Robotic Arm Movement with Reservoir Cell Assemblies

Before Learning
of Cell Assemblies



After Learning
of Cell Assemblies



One decade of raising the complexity of neural control and self-organization

- Tao Geng)
- Poramate Manoonpong
- Christian Tetzlaff
- Tomas Kulvicius
- Sakya Dasgupta
- Minija Tamosiunaite
- And many others

Thanks

Funded by EU-FP7, EU-H2020,
Bernstein Center for Computational Neuroscience (BMBF),
DFG,