Workshop Program:

09:30	Workshop start
09:30-09:45	Brief Introduction, announcements, Poramate
Six-legged and multi-legged locomotion	
09:45-10:15	Six legged locomotion: A comparative study of different insect models, Amir Ayali
10:15-10:45	Biological inspired approaches to robot control try to mimic the motor performance found in animals, Malte Schilling
10:45-11:15	Coffee break
11:15-11:45	Simple model analysis of the effect of sensory feedback on multi-legged interlimb coordination: Existence of direct, retrograde and source wave gaits, Yuichi Ambe
11:45-12:15	Improvement of turning maneuverability of a multi legged robot by the straight walk instability, Shinya Aoi
12:15-12:45	From a dung beetle to a multifunctional robot: A bio-inspired approach, Poramate Manoonpong
12:45-14:00	Lunch
Four-legged locomotion	
14:00-14:30	Dynamic locomotion in legged machines, Alexander Spröwitz
14:30-15:00	Bio-inspired gait transition for quadruped robots, Yasuhiro Fukuoka
15:00-15:30	Biological approach and engineering approach for walking, Gen Endo
15:30-16:00	Coffee break
Two-legged locomotion	
16:00-16:30	Muscular Skeletal Structure and Adaptive Bipedal Walking, Koh Honsoda
16:30-17:00	Inter and intralimb coordination for adaptive bipedal walking: Tegotae-based approach, Dai Owaki
17:00-17:30	Discussion & closing, Shinya