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► **To cite this version:**

Julien Serres, Franck Ruffier, Nicolas Franceschini. A bio-inspired robot accounts for insect behavior. 16th European Conference en Eye Movement (ECEM), Aug 2011, Marseille, France. hal-02194432

**HAL Id: hal-02194432**

**<https://hal.science/hal-02194432>**

Submitted on 25 Jul 2019

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# A bio-inspired robot accounts for insect behavior

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Based on a biorobotic approach developed in our laboratory over the past 25 years, we have built several terrestrial and aerial vehicles controlled on the basis of Optic Flow (OF) cues [Rev. Franceschini, 2009, *Acta Futura*, 3, 15-34]. The LORA III robot is a miniature hovercraft that perceives the environment by means of neuromimetic OF sensors. To understand how honeybees may follow a wall [Serres et al., 2008, *Naturwissenschaften*, 95(10), 1181-1187], center along a corridor and adjust their speed to the corridor width [Srinivasan et al., 1996, *J. Exp. Biol.*, 199, 237-244], we developed a vision-based autopilot, which consists of a *dual OF regulator* controlling the hovercraft's *translations* [Serres et al., 2008, *Autom. Rob.*, 25(1-2), 103-122]. Yaw disturbances introduce adverse *rotational* OF component, which do not depend on the distance to obstacles. The robot's gaze therefore requires to be stabilized in yaw to make sure the robot will measure only the *translational* OF component, as suggested by several insects [Wagner, 1986, *Phil. Trans. R. Soc. Lond. B*, 337, 527-551] [Boeddeker & Hemmi, 2010, *Phil. Trans. R. Soc. Lond. B*, 277(1685), 1209-1217] [Zeil et al., 2008, *Current Biol.*, 18(8), 320-323]. Our biorobotic approach allowed us to better appreciate the fundamental role of gaze locking in flying animals.