\( F_{self}(c) \) distance covered in the self-model

\( b_{self}(c) \) behavior description of the self-model (e.g. contacts)

\( \hat{T}(b_{self}(c)) \) approximated transferability corresponding to controller \( c \)

MOEA

\( \max \left\{ F_{self}(c), \hat{T}(b_{self}(c)) \right\} \)

\( c^* \) randomly selected in the population

(B) Update of transferability, every \( N \) iterations

\( F_{real}(c^*) \) distance covered on the robot (internal measures)

update of approx. transferability \( \hat{T} \) by regression