Key Development Points

Our robot is the ANYmal quadruped with the powerful DynaArm manipulator mounted on top, with custom software for locomotion, navigation, and leader-follower arm control.

Team Introduction

Our lab focuses on robot capabilities in challenging environments, and disaster response provides an interesting and socially beneficial application for our research.

We will continue advancing our manipulation and navigation capabilities in tough environments, such as disaster response

Role	Name	Affiliation/Position	Areas of expertise, research fields
Team Leader/Pilot	Yuni Fuchioka	ETH Zürich, PhD Student	Teleoperated Legged Manipulation
Advisor/Locomotion Engineer	Takahiro Miki	Google DeepMind, Research Scientist	Perceptive Locomotion
Inspection Engineer/Pilot	Maximum Wilder-Smith	ETH Zürich, Research Engineer	Computer Vision, Virtual Reality
Mechanical/Manipulation Engineer	Oliver Fischer	ETH Zürich, Research Engineer	Disaster and Space Robotics
Navigation Lead	Fan Yang	ETH Zürich, PhD Student	End-to-End Local Navigation
Navigation Engineer	Marco Trentini	ETH Zürich, Research Engineer	Global Path Planning
Advisor/Software Engineer	Andrei Cramariuc	ETH Zürich, PostDoc	Legged Manipulation
Software Engineer	Aravind Elanjimattathil Vijayan	ETH Zürich, PhD Student	Industrial Legged Manipulation

Contact Information   Robotic Systems Lab, Department of Mechanical and Process Engineering (D-MAVT), ETH Zürich

Websites, etc.   https://rsl.ethz.ch/