

ANTON BREDENBECK

PhD Researcher

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EXPERIENCE

Ph.D. Researcher

TU Delft

June 2022 – now

Delft, Netherlands

Under the supervision of Salua Hamaza and Cosimo Della Santina I am conducting research on how drones can better exploit contact in guidance, navigation and control. See below for a list of publications & visit my website for project digests.

I also actively contribute to teaching endeavors by supervising master students, creating and conducting exercises, and participating in outreach activities.

Research & Teaching Assistant

Julius-Maximilians University

June 2020 – August 2021

Würzburg, Germany

- Member of the project group DAEDALUS where I worked on design, software development, and manufacturing of the prototype measurement system for 3D point-cloud creation.
- TA for "Advanced Sensory Systems and Sensor Data Processing".

Research Assistant

DFKI

October 2020 – December 2020

Bremen, Germany

Staff member in the project Fast & Slow. Software development for a ROS2 interface to enable reinforcement learning of TurtleBots.

Working Student

Zentrum für Telematik e.V.

October 2019 – December 2019

Würzburg, Germany

GNSS-sensorevaluation and rudimentary PCB design and component placement.

Research Assistant

Finish Geospatial Research Institute

March 2019 – August 2019

Helsinki, Finland

Development of a GNSS-interference detection-and surveillance service (GNSS-Finland) as well as development of a "Dual Frequency Measurement Correction" System for Android Devices.

STRENGTHS

Hard-working Resilient Thorough

C/C++ Python Julia MATLAB ROS 2 ROS

Robotics Design Control Estimation

EDUCATION

Ph.D. in Robotics

Biomorphic Intelligence Lab, TU Delft

June 2022 – now

Delft, Netherlands

I work on "*Tactile-driven Control for Aerial Robots*". Thereby I want to enable **aerial robots** to robustly and safely **interact** with the world around them, while exploiting contact as a source of information.

M.Sc. in Satellite Technology

Julius-Maximilians University

2019 – 2022

Würzburg, Germany

Graduate with honors with the maximum grade (1,0).

- Six months specialization in Robotics & Control @Czech Technical University in Prague
- Master thesis @ESA/ESTEC working on trajectory optimization and control for a free floating platform. The results were published at IROS 2022 in Kyoto.

B.Sc. in Aerospace Computer Science

Julius-Maximilians University

2016 – 2019

Würzburg, Germany

Six month internship at the Finish Geospatial Research Institute in Helsinki, Finland.

REFEREES

Prof. Dr. Salua Hamaza

@ Biomorphic Intelligence Lab, Assistant Professor, TU Delft
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Prof. Dr. Mark Mueller

@ HiPeR Lab, Associate Professor, UC Berkeley
✉ mwm@berkeley.edu

Prof. Dr. Cosimo Della Santina

@ Cognitive Robotics, Assistant Professor, TU Delft
✉ c.dellasantina@tudelft.nl

PUBLICATIONS

Journal Articles

- A. Bredenbeck, C. Della Santina, and S. Hamaza, "An aerial manipulator with a compliant finger embodies touch for navigation," *[UNDER REVIEW] IEEE Robotics and Automation Letters (RA-L)*, 2024.
- F. Arzberger, J. Zevering, A. Bredenbeck, D. Borrmann, and A. Nüchter, "Unconventional trajectories for mobile 3d scanning and mapping," *Autonomous Mobile Mapping Robots*, 2022.
- F. Arzberger, A. Bredenbeck, J. Zevering, D. Borrmann, and A. Nüchter, "Towards spherical robots for mobile mapping in human made environments," *ISPRS Open Journal of Photogrammetry and Remote Sensing*, p. 100 004, 2021.

Conference Proceedings

- F. Arzberger, J. Zevering, A. Bredenbeck, D. Borrmann, and A. Nüchter, "Mobile 3d scanning and mapping for freely rotating and vertically descended lidar," in *2022 IEEE International Symposium on Safety, Security, and Rescue Robotics (SSRR)*, IEEE, 2022, pp. 122–129.
- A. Bredenbeck, C. Della Santina, and S. Hamaza, "End-effector contact force estimation for aerial manipulators," in *IROS 2022 Workshop on Mobile Manipulation and Embodied Intelligence (MOMA): Challenges and Opportunities*, 2022.
- A. Bredenbeck, S. Vyas, W. Suter, et al., "Finding and following optimal trajectories for an overactuated floating robotic platform," 2022.
- A. Bredenbeck, S. Vyas, M. Zwick, D. Borrmann, M. Olivares-Mendez, and A. Nüchter, "Trajectory optimization and following for a three degrees of freedom overactuated floating platform," in *2022 IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, IEEE, 2022, pp. 4084–4091.
- J. Zevering, D. Borrmann, A. Bredenbeck, and A. Nüchter, "The concept of rod-driven locomotion for spherical lunar exploration robots," in *2022 IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, IEEE, 2022, pp. 5656–5663.
- D. Borrmann, A. Nüchter, A. Bredenbeck, et al., "Lunar caves exploration with the daedalus spherical robot," in *52nd Lunar and Planetary Science Conference*, 2021, p. 2073.
- R. Pozzobon, A. Rossi, S. Ferrari, et al., "Marius hills skylight hazard characterization as a possible landing site for lunar subsurface exploration," in *52nd Lunar and Planetary Science Conference*, 2021, p. 1886.
- A. P. Rossi, F. Maurelli, V. Unnithan, et al., "Daedalus-descent and exploration in deep autonomy of lava underground structures: Open space innovation platform (osip) lunar caves-system study," 2021.
- J. Zevering, A. Bredenbeck, F. Arzberger, D. Borrmann, and A. Nüchter, "Imu-based pose-estimation for spherical robots with limited resources," in *2021 IEEE International Conference on Multisensor Fusion and Integration for Intelligent Systems (MFI)*, IEEE, 2021, pp. 1–8.
- S. Nikolskiy, A. Bredenbeck, T. Rikkinen, et al., "Gnss signal quality monitoring based on a reference station network," in *2020 European Navigation Conference (ENC)*, IEEE, 2020, pp. 1–10.
- J. Zevering, A. Bredenbeck, F. Arzberger, D. Borrmann, and A. Nüchter, "Luna - a laser-mapping unidirectional navigation actuator," in *International Symposium on Experimental Robotics*, Springer, Cham, 2020, pp. 85–94.