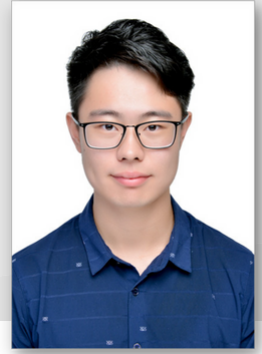


Chenhao Li

April 28, 1997 | Rämistrasse 101, 8092 Zurich
<https://breadli428.github.io/> | chenhli@ethz.ch



EDUCATION

ETH AI Center, Zurich, Switzerland

Ph.D. at Robotic Systems Lab and Learning & Adaptive Systems Group

ETH Zurich, Zurich, Switzerland

M.Sc. in Robotics, Systems and Control, 5.98 / 6.0

Tongji University, Shanghai, China

B.Eng. in Mechanical Engineering, 4.93 / 5.0

11.2023 - present

Doctoral Fellowship

09.2020 - 08.2023

ETH Medal

09.2015 - 07.2020

Excellent Graduate

WORK EXPERIENCE

Visiting Researcher, Massachusetts Institute of Technology, United States

01.2023 - 08.2023

- Self-supervised structured robot dynamics learning (PAE, FLD).
- Intelligent adaptive curriculum learning in continuous task space (ALP-GMM).

Research Intern, Max Planck Institute for Intelligent Systems, Germany

04.2022 - 12.2022

- Agile robot skill development with generative adversarial imitation learning (AMP, WASABI).
- Intrinsic skill diversification through mutual information maximization (DIAYN, DADS, DISDAIN, CASSI).
- Morphology-inspired robot learning with graph neural networks (GCN, NerveNet).

PUBLICATIONS

Robotic World Model: A Neural Network Simulator for Robust Policy Optimization in Robotics

Chenhao Li, Andreas Krause, Marco Hutter

preprint

- *model-based reinforcement learning method for robust policy optimization*

Toward Task Generalization via Memory Augmentation in Meta-Reinforcement Learning

Kaixi Bao, Chenhao Li, Yarden As, Andreas Krause, Marco Hutter

preprint

- *memory-enhanced meta-reinforcement learning for improved task generalization*

Learning More With Less:

Sample Efficient Dynamics Learning and Model-Based RL for Loco-Manipulation

preprint

Benjamin Hoffman, Jin Cheng, Chenhao Li, Stelian Coros

- *uncertainty-informed dynamics learning for efficient policy learning*

DFM: Deep Fourier Mimic for Expressive Dance Motion Learning

ICRA 2025

Ryo Watanabe, Chenhao Li, Marco Hutter

- *efficient motion representation with frequency-domain parameterization for expressive policy learning*

<u>FLD: Fourier Latent Dynamics for Structured Motion Representation and Learning</u>	ICLR 2024
Chenhao Li , Elijah Stanger-Jones, Steve Heim, Sangbae Kim	spotlight
<ul style="list-style-type: none"> spatial-temporal representation of high-dimension, long-horizon, highly nonlinear inputs 	
<u>Learning Diverse Skills for Local Navigation under Multi-constraint Optimality</u>	ICRA 2024
Jin Cheng, Marin Vlastelica, Pavel Kolev, Chenhao Li , Georg Martius	
<u>Versatile Skill Control via Self-supervised Imitation of Unlabeled Mixed Motions</u>	ICRA 2023
Chenhao Li , Sebastian Blaes, Pavel Kolev, Marin Vlastelica, Jonas Frey, Georg Martius	
<ul style="list-style-type: none"> unsupervised skill discovery in generative adversarial demonstration learning 	
<u>Learning Agile Skills via Adversarial Imitation of Rough Partial Demonstrations</u>	CoRL 2022 oral
Chenhao Li , Marin Vlastelica, Sebastian Blaes, Jonas Frey, Felix Grimminger, Georg Martius	best paper finalist
<ul style="list-style-type: none"> agile skill learning from limited demonstrations 	

AWARDS

ETH Medal (0.5%)	04.2023
ETH AI Center Doctoral Fellowship (1%)	03.2023
Best Paper Award Finalist (CoRL 2022)	12.2022
Swiss-European Mobility Scholarship	10.2022
ETH Scholarship	02.2022, 02.2023
National Scholarship (0.2%)	11.2018, 11.2016

INVITED TALKS

JSK Lab, University of Tokyo, Japan	01.2025
Sony AI, Japan	01.2025
Toyota Research Institute, United States	03.2024
Shirley Ryan AbilityLab, Northwestern University, United States	03.2024
The Robotics Institute, Carnegie Mellon University, United States	03.2024
AI4CE Lab, New York University, United States	03.2024
Learning & Adaptive Systems Group, ETH Zurich, Switzerland	11.2023
Biomimetic Robotics Lab, Massachusetts Institute of Technology, United States	01.2023
Machines in Motion Laboratory, New York University, United States	12.2022
Robotic Systems Lab, ETH Zurich, Switzerland	08.2022

REVIEWER SERVICE

IROS, ICRA, CoRL, RA-L, RLC, ICLR, RSS, ICML	2023 - present
--	----------------
