

Michel Aractingi

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PhD student at NAVER LABS Europe and LAAS-CNRS Gepetto Team

Education

LAAS-CNRS & University of Toulouse

Ph.D. in Robotics and Artificial Intelligence

◦ Advisors: Philippe Soueres (LAAS), Tomi Silander (NaverLabs Europe)

Toulouse, France

2020 – present

Grenoble Institute of Technology

M.Sc. in Computer Science; Avg: 15/20 (top 5%)

◦ Includes a two month internship at FabLab in Grenoble

◦ Includes a six month internship at Inria Grenoble

Grenoble, France

2016 – 2018

University of Balamand

B.Sc. in Electrical Engineering; GPA: 3.13 (top 5%)

Balamand, Lebanon

2013 – 2016

Research and Work Experience

Naver Labs Europe and LAAS-CNRS

Doctoral Researcher

◦ Worked on applying reinforcement learning for agile quadruped locomotion.

◦ Designed and deployed learned controllers on the Solo12 robot and MIT's Mini-Cheetah in complex outdoor environments.

Grenoble/Toulouse, France

July 2020 – present

Naver Labs Europe

Research Engineer

◦ Worked in the robot navigation project. The subject involved studying the generalization of learned visual navigation policies in indoor and crowded environments.

Grenoble, France

November 2018 – June 2020

Inria Center at the University Grenoble Alpes

Research Intern

◦ Worked in the Thoth team, supervised by professor Cordelia Schmid. The subject of the thesis was about imitation learning of vision-based manipulation skills.

Grenoble, France

February 2018 – July 2018

Publications

◦ A Hierarchical Scheme for Adapting Learned Quadruped Locomotion, *preprint*

M. Aractingi, P.A. Léziart, T. Flayols, J. Perez, T. Silander and P. Soueres.

◦ Controlling the Solo12 Quadruped Robot with Deep Reinforcement Learning, *preprint*

M. Aractingi, P.A. Léziart, T. Flayols, J. Perez, T. Silander and P. Soueres.

◦ DiPCAN: Distilling privileged information for crowd-aware navigation, *RSS 2022*, Best paper award nominee

G. Monaci, M. Aractingi and T. Silander.

◦ Learning to Adapt the Trotting Gait of the Solo Quadruped, *preprint*

M. Aractingi, P.A. Léziart, T. Flayols, J. Perez, T. Silander and P. Soueres.

◦ Improving the generalization of visual navigation policies using invariance regularization, *ICML 2019*, RL4RealLife workshop

M. Aractingi, C. Dance, J. Perez and T. Silander.

References

Contact my advisors and colleagues: Tomi Silander (Naver Labs Europe), Julien Perez (Naver Labs Europe), Philippe Soueres (LAAS-CNRS), Thomas Flayols (LAAS-CNRS).