

Maurice Rahme

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Summary

- Robotician at Boston Dynamics experienced in Motion Planning techniques
- Helped take Stretch from a prototype to a real product with >6 million customer boxes moved to date
- Expanding into Mechanistic Interpretability to improve the control-ability and performance of applied ML

Education

Northwestern University, M.Sc. in Robotics - GPA: 3.95/4.0 Sep 2020
The University of Edinburgh, B.Eng in Mechatronics - First Class, GPA: 4.0/4.0 Jun 2019

Experience

Staff Robotics Engineer, Boston Dynamics – Detroit, MI (Remote) Jan 2022 - Present

- Tech Lead for Stretch Motion Planning and technical mentor to 5 colleagues
- Currently implementing Hybrid ML/Optimal Control scheme to upgrade performance
- Enabled highly dextrous motion generation as seen at [MODEX](#)
- Created novel methods for extracting trapped payloads in complex environments
- Increased Stretch's payload capacity from 15kg to 23kg using Wrench Minimization
- Enhanced handling of poorly supported cargo through sag-predictive collision avoidance
- Boosted Stretch trajectory speed by >2x

Senior Robotics Engineer, Boston Dynamics – Waltham, MA Nov 2020 - Jan 2022

- Implemented Directed Graph search library (A*, D*Lite)
- Wrote Task-Space Controller for Stretch Base Driving
- Designed robot manufacturing SW, enabling the production of >100 Stretch robots in 3 years

Publications

Linear Policies are Sufficient to Enable Low-Cost Quadrupedal Robots to Traverse Rough Terrain - 10.1109/IROS51168.2021.9636011 Sep 2021

Projects

Learning Quadruped Locomotion from Scratch

- Architected novel Reinforcement Learning method for Terrain Adaptation
- Designed and open-sourced quadruped that can be built for under \$600

Motion Planning in C++

- Implemented scalable Probabilistic Roadmap and Grid Map
- Developed Library containing A*, Theta*, D*Lite, Potential Fields, MPPI

EKF-SLAM on Turtlebot3

- Developed 2D Kinematics library in C++ for Differential Drive robots
- Performed EKF SLAM with Unknown Data Association

Technologies

Languages/Libraries: C++, Python, Eigen, Pytorch, Pandas, ROS, Gazebo, Mujoco, Pybullet, URDF/XACRO, Git

Technical: Manipulation, Optimal Control, State Estimation, Machine Learning