

Thomas Stastny

Aerial-Robotics Researcher

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Summary

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I am a field roboticist with a specialization in autonomy for flying systems. I have a particular passion for (remote) field work, developing practical algorithms for the purpose of deploying fixed-wing, multirotor, and hybrid vertical-take-off-and-landing (VTOL) unmanned aerial vehicles (UAVs) in challenging conditions or for complex tasks. My primary research motivations are geared towards enabling safe, reliable, and useful(!) autonomous vehicle operations in environments where humans can or should not go.

Grants: Authorship of **successful** research proposals with funding totaling **>USD 1.7M**.

Publications: As of March 15, 2021, peer-reviewed publication count: **31**, h-index: **12**, citation count: **550** (source: [Google Scholar](#)).

Mentorship: **Supervision** of **4** Ph.D. students and **50+** M.Sc. and B.Sc. theses. **Lecturer** for 2 M.Sc. courses. **TA** for 2 B.Sc. courses.

Field experience: Organization/contributions of/to aerial-robotic field-campaigns in the Arctic, Antarctic, Brazilian Amazon, and Swiss/Italian Alps.

Education

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- 2014 - 2020 **ETH Zürich**, Zürich, Switzerland
Ph.D. in Robotics, supervised by Prof. Roland Siegwart in the *Autonomous Systems Lab*
Dissertation: *Low-Altitude Control and Local Re-Planning Strategies for Small Fixed-wing UAVs*
- 2012 - 2014 **University of Kansas**, Lawrence, KS, USA
M.Sc. in Aerospace Engineering (*with Honors*), GPA: 4.0/4.0
- 2012 **TU Delft**, Delft, Netherlands
Coursework in Systems & Control and Aerospace Engr. M.Sc. Programs
- 2008 - 2012 **University of Kansas**, Lawrence, KS, USA
B.Sc. in Aerospace Engineering, GPA: 3.7/4.0

Research Experience

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- Since 10/2020 **Autonomous Systems Lab (ASL), ETH Zürich** – Post-Doctoral Researcher
- Supervise and coordinate PhD and Masters student research activities related to fixed-wing UAVs, recent results including:
 - automatic tilt-wing UAV control, stabilized deep stalled flight, span/chord-wise wing-fitted pressure sensor arrays for in-flight airflow measurement, design and wind tunnel characterization of a winged omni-directional UAV
 - Project lead for on-going funded projects:
 - high-speed vision-based payload recovery using fixed-wing UAVs
 - precision sensor placement and recovery on remote glaciers using a long-range tilt-wing UAV
 - “AvalMapper”, developing an autonomous aerial detection and mapping system for high-alpine avalanches utilizing machine learned classification methods and informative path planning for reliably reconstructable snow-depth maps
- 2014 - 2020 **Autonomous Systems Lab (ASL), ETH Zürich** – PhD Research Assistant
- Core researcher on EU search-and-rescue robotics projects *SHERPA* and *ICARUS*, organizing multiple university and industry partners in collaborative multi-robotic field demonstrations.
 - Interfaced with customers and industry partners within the ESA precision-farming project *SOLAR3* to deliver a reliable automatic, multi-hour endurance, solar-powered surveying drone solution to non-expert end-users in Switzerland and Ukraine.
 - Developed and deployed:
 - robust, wind-aware estimation, guidance, and control algorithms for UAVs in extreme wind conditions
 - nonlinear model predictive control (NMPC) schemes for fixed-wing UAVs including objectives for aggressive 3D path following, actuator fault tolerance, stall prevention, and vision-based terrain feedback
 - a semi-automated system identification pipeline for fixed-wing UAVs (iterated EKF, nonlinear parameter optimization)
 - Conducted performance optimization and developed automatic take-off, landing, and cruise control design for the *AtlantikSolar* UAV, resulting in an **81.5 hour endurance world record** solar-powered flight for aircraft <50kg https://youtu.be/8m4_NpTQn0E and 26 hour, fully autonomous, search-and-rescue payload equipped flight <https://youtu.be/8m76Mx9m2nM>
- 2012 - 2014 **Center for Remote Sensing of Ice Sheets (CRENIS), University of Kansas** – Masters Research Assistant
- Conducted research on control and planning for fixed-wing UAVs including multi-agent avoidance and formation strategies.
 - Contributed to the design, integration, and **Antarctic deployment** of a polar-conditioned fixed-wing UAV with integrated dual-frequency ground-penetrating radar.

Programming C/C++, Python (NumPy, SciPy), Matlab/Simulink • **Software** Linux, Robotic Operating System (ROS), Embedded Systems, Git, CI, Unigraphics NX (CAD) • **Hardware** 3D Prototyping, Radio controlled (RC) piloting of small fixed-wing aircraft and multi-copters

Field Projects [\(to top\)](#)

- **Supervised/Managed** student/engineering work on platform and payload development towards autonomous, beyond visual line-of-sight (BVLOS), drone-based deployment of GNSS monitoring stations on the **Gorner Glacier**, Switzerland. (2019) video: <https://youtu.be/1tvYj1aGEUc>
- Contributed regulatory documentation and flight-stack verification for the *first* networked (via industry partners Swisscom, INVOLI, and v2sky), BVLOS flight in Switzerland over Lake Neuchâtel. (2019) video: <https://youtu.be/ks-TiJP3dxs>
- **Organized/Lead** UAV operations in **Northwest Greenland** for a glacier monitoring field campaign, resulting in *first-ever* autonomous, BVLOS, solar-powered flights of a UAV in a polar region. (2017) website: <http://sun2ice.ethz.ch>, video: https://youtu.be/wyS6W1t_ryQ
- **Organized/Lead** field operations together with Swissnex Brazil and Brazilian Civil Aviation Authorities resulting in *first-ever* solar-powered flights of a UAV over the **Amazon rainforest** and the aerial monitoring/mapping of an oil spill on the Rio Pará.
- **8-week deployment** as mission planner and ground station operator for autonomous, BVLOS flights of a radar-integrated UAV in **Antarctica**, resulting in *first-ever* glacial bed-rock sounding via a UAV. (2014) <https://cresis.ku.edu/content/research/field-programs/antarctica#2013>

Grants [\(to top\)](#)

Proposals Under Review

2021 Safe Self-Calibration of Hybrid Aerial Vehicles
Role: **Co-Author**. PI: R. Siegwart. *Amazon Research Awards (ARA)*. **USD 100,000**

Funded Proposals

2021 Autonomous Deployment of GNSS Stations on Polar Outlet Glaciers Using a Long-Range, Tilt-Wing UAV
PI: **T. Stastny**. *Swiss Polar Institute (SPI) Technogrant*. **CHF 50,000 (USD 53,529)**

2021-2023 AvalMapper: Remote Avalanche Mapping with Long Flight Duration UAVs
Role: **Lead author**. PI: R. Siegwart. *ETH Research Grants*. **CHF 392,900 (USD 420,634)**

2019-2020 Drop & Recovery Drones
Role: **Lead author**. PI: R. Siegwart. *Armasuisse S+T*. **CHF 300,000 (USD 321,176)**

2018 Sensory Enhanced Perception and Control for Autonomous Operation of Fixed-Wing UAVs in Unstructured Environments
Role: **Lead author**. PI: R. Siegwart. *Armasuisse S+T*. **CHF 150,000 (USD 160,588)**

2018 Predicting the Weather: On-board Forecasting of Local 3D Wind Fields for Autonomous and Environment-aware Operation of Unmanned Aerial Vehicles
Role: **Lead author**. PI: R. Siegwart. *Intel University-Industry Research Corporation (UIRC)*. **USD 150,000**

2017-2019 Sun-to-Ice: Monitoring the Fracturing of Calving Glaciers from Solar-Powered UAVs in Polar Regions
Role: **Co-Lead author**. PI: G. Jouvet. *ETH Research Grants*. **CHF 426,500 (USD 456,606)**

2014-2016 Multi-Agent Airborne Laboratory for Cryospheric Remote Sensing
Role: **Co-author**. PI: S. Keshmiri. *Paul G. Allen Family Foundation*. **USD 200,000**

Mentorship & Teaching [\(to top\)](#)

- **Supervised** 4 PhD Students (ongoing), 24 Masters Theses, 18 Masters Semester Theses, and 14 Bachelor Theses at ETH Zürich. (2014 – Present)
- **Coached** 3 ETH Zürich Focus Projects – teams of 8-12 B.Sc. students who develop a robotic product from A to Z:
 - *Dipper* – a flying, diving, swimming, and re-emerging, swept-wing UAV. video: https://youtu.be/q_9tSHTW1xE
 - *ftero* – a VTOL UAV for airborne wind energy (year 1 and 2)
 - *VertiGo* – a wall-riding robot. Resulted in a patent. video: <https://youtu.be/KRYT2kYbgo4>
- **Co-Lecturer** for ETH Zürich M.Sc. course “Robot Dynamics” (2015–Present).
- **Guest Lecturer** for University of Kansas Aerospace M.Sc. course “Optimal Control” (2013).
- **Teaching assistant** for University of Kansas B.Sc. courses “Introductory Topics in Mathematics” and “Elementary Statistics”. (2010 – 2012)

Awards [\(to top\)](#)

- **O. Hugo Schuck Best Paper Award** (2018) for American Control Conference (ACC) paper: “Gone with the wind: Nonlinear Guidance for Small Fixed-wing Aircraft in Arbitrarily Strong Windfields”. <http://a2c2.org/awards/o-hugo-schuck-best-paper-award>
- **United States Department of Defense Antarctica Service Medal** (2014)
- **University of Kansas Aerospace Undergraduate Researcher Award** (2012)

Reviewer	IEEE Transactions on Robotics, IEEE Transactions on Aerospace and Electronic Systems, Springer Journal of Intelligent and Robotic Systems, IEEE Robotics and Automation Letters (RA-L), IEEE Control Systems Letters (L-CSS), IEEE International Conference on Robotics and Automation (ICRA), IEEE/RSJ International Conference on Robots and Intelligent Systems (IROS), IEEE International Conference on Unmanned Aircraft Systems (ICUAS)
Associate Editor	Frontiers in Robotics and AI, Field Robotics (2020)
Organizer	Co-Organizer of ICUAS Tutorial: <i>Autonomous Navigation for Aerial Robotics in Extreme Environments: From Subterranean Environments to the Arctic</i> (2018)

Publications (to top)

Organized by type and date. Metrics found on Google Scholar: <https://scholar.google.ch/citations?user=R5Fs1A4AAAAJ&hl=en>.

Journal Papers

1. D. Malyuta, C. Brommer, D. Hentzen, **T. Stastny**, R. Siegwart, and R. Brockers. “Long-duration Fully Autonomous Operation of Rotorcraft Unmanned Aerial Systems for Remote-sensing Data Acquisition”. *Journal of Field Robotics (JFR)*. 2020.
2. D. Rohr, **T. Stastny**, S. Verling, and R. Siegwart. “Attitude and Cruise Control of a VTOL Tiltwing UAV”. *IEEE Robotics and Automation Letters*. 2019. https://youtu.be/pSXEnHUY2_4
3. T. Hinzmann, **T. Stastny**, C. Cadena, R. Siegwart, and I. Gilitschenski. “Free LSD: Prior-free Visual Landing Site Detection for Autonomous Planes”. *IEEE Robotics and Automation Letters*. 2018. <https://youtu.be/SOpYirBwHtQ>
4. P. Oettershagen, **T. Stastny**, T. Hinzmann, K. Rudin, T. Mantel, A. Melzer, B. Wawrzacz, G. Hitz, and R. Siegwart. “Robotic Technologies for Solar-powered UAVs: Fully Autonomous Updraft-aware Aerial Sensing for Multiday Search-and-rescue Missions”. *Journal of Field Robotics (JFR)*. 2018. <https://youtu.be/8m76Mx9m2nM>
5. P. Oettershagen, A. Melzer, Mantel, K. Rudin, **T. Stastny**, B. Wawrzacz, T. Hinzmann, S. Leutenegger, K. Alexis, and R. Siegwart. “Design of Small Hand-launched Solar-powered UAVs: From Concept Study to a Multi-day World Endurance Record Flight”. *Journal of Field Robotics (JFR)*. 2017. https://youtu.be/8m4_NpTQn0E
6. **T. Stastny**, G. Garcia, S. Keshmiri. “Collision and Obstacle Avoidance in Unmanned Aerial Systems Using Morphing Potential Field Navigation and Nonlinear Model Predictive Control”. *Journal of Dynamic Systems, Measurement, and Control*. 2015.
7. G. Garcia, S. Keshmiri, **T. Stastny**. “Nonlinear Model Predictive Controller Robustness Extension for Unmanned Aircraft”. *International Journal of Intelligent Unmanned Systems*. 2015.
8. G. Garcia, S. Keshmiri, **T. Stastny**. “Robust and Adaptive Nonlinear Model Predictive Controller for Unsteady and Highly Nonlinear Unmanned Aircraft”. *IEEE Transactions on Control Systems Technology*. 2014.

Book Chapters

1. M. Kamel, **T. Stastny**, K. Alexis, R. Siegwart. “Model Predictive Control for Trajectory Tracking of Unmanned Aerial Vehicles Using Robot Operating System”. *Robot Operating System (ROS), The Complete Reference (Volume 2)*. 2017.

Peer-Reviewed Conference Papers

1. C. Olsson, S. Verling, **T. Stastny**, and R. Siegwart. “Full Envelope System Identification of a VTOL Tailsitter UAV”. *AIAA Guidance, Navigation, and Control (GNC) Conference*. 2021.
2. M. Harms, N. Kaufmann, F. Rockenbauer, N. Lawrance, **T. Stastny**, and R. Siegwart. “Differential Sweep Attitude Control for Swept Wing UAVs”. *International Conference on Unmanned Aircraft Systems (ICUAS)*. 2020.
3. **T. Stastny** and R. Siegwart. “On Flying Backwards: Preventing Run-away of Small, Low-speed, Fixed-wing UAVs in Strong Winds”. *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*. 2019. <https://youtu.be/oM690LQ29kM>
4. D. Hentzen, **T. Stastny**, R. Siegwart, and R. Brockers. “Disturbance Estimation and Rejection for High-Precision Multirotor Position Control”. *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*. 2019. <https://youtu.be/-1PvZ5YBluw>
5. **T. Stastny**, E. Ahbe, M. Dangel, and R. Siegwart. “Locally Power-optimal Nonlinear Model Predictive Control for Fixed-wing Airborne Wind Energy”. *American Control Conference (ACC)*. 2019.
6. S. Fuhrer, S. Verling, **T. Stastny**, and R. Siegwart. “Fault-tolerant Flight Control of a VTOL Tailsitter UAV”. *IEEE International Conference on Robotics and Automation (ICRA)*. 2019. <https://youtu.be/tmJQ2r2AOwk>
7. J. Lee, T. Muskardin, C. Pacz, P. Oettershagen, **T. Stastny**, I. Sa, R. Siegwart, and K. Kondak. “Towards Autonomous Stratospheric Flight: A Generic Global System Identification Framework for Fixed-Wing Platforms”. *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*. 2018.

8. **T. Stastny** and R. Siegwart. “Nonlinear Model Predictive Guidance for Fixed-wing UAVs Using Identified Control Augmented Dynamics”. *International Conference on Unmanned Aircraft Systems (ICUAS)*. 2018.
9. L. Furieri, **T. Stastny**, L. Marconi, R. Siegwart, and I. Gilitschenski. “Gone with the Wind: Nonlinear Guidance for Small Fixed-wing Aircraft in Arbitrarily Strong Windfields”. *American Control Conference (ACC)*. 2017.
10. S. Verling, **T. Stastny**, G. Bättig, K. Alexis, and R. Siegwart. “Model-based Transition Optimization for a VTOL Tailsitter”. *IEEE International Conference on Robotics and Automation (ICRA)*. 2017.
11. Y. Demetri, S. Verling, **T. Stastny**, A. Melzer, and R. Siegwart. “Model-based Wind Estimation for a Hovering VTOL Tailsitter UAV”. *IEEE International Conference on Robotics and Automation (ICRA)*. 2017.
12. **T. Stastny**, A. Dash, and R. Siegwart. “Nonlinear MPC for Fixed-wing UAV Trajectory Tracking: Implementation and Flight Experiments”. *AIAA Guidance, Navigation, and Control (GNC) Conference*. 2017.
13. P. Oettershagen, A. Melzer, T. Mantel, K. Rudin, **T. Stastny**, B. Wawrzacz, T. Hinzmann, K. Alexis, and R. Siegwart. “Perpetual Flight with a Small Solar-powered UAV: Flight Results, Performance Analysis and Model Validation”. *IEEE Aerospace Conference*. 2016.
14. T. Hinzmann, **T. Stastny**, G. Conte, P. Doherty, P. Rudol, M. Wzorek, I. Gilitschenski, E. Galceran, and R. Siegwart. “Collaborative 3D Reconstruction Using Heterogeneous UAVs: System and Experiments”. *International Symposium on Experimental Robotics (ISER)*. 2016.
15. P. Doherty, J. Kvarnström, P. Rudol, M. Wzorek, G. Conte, C. Berger, T. Hinzmann, **T. Stastny**. “A Collaborative Framework for 3D Mapping Using Unmanned Aerial Vehicles”. *International Conference on Principles and Practice of Multi-Agent Systems*. 2016.
16. Oettershagen, **T. Stastny**, T. Mantel, A. Melzer, K. Rudin, P. Gohl, G. Agamennoni, K. Alexis, and R. Siegwart. “Long-Endurance Sensing and Mapping using a Hand-Launchable Solar-Powered UAV”. *Field and Service Robotics (FSR)*. 2015.
17. A. Vempati, G. Agamennoni, **T. Stastny**, and R. Siegwart. “Victim Detection from a Fixed-Wing UAV: Experimental Results”. *International Symposium on Visual Computing (ISVC)*. 2015.
18. **T. Stastny**, G. Garcia, S. Keshmiri. “Robust Three-Dimensional Collision Avoidance for Fixed-Wing Unmanned Aerial Systems”. *AIAA Guidance, Navigation, and Control (GNC) Conference*. 2015.
19. **T. Stastny**, R. Lykins, S. Keshmiri. “Nonlinear Parameter Estimation of Unmanned Aerial Vehicles in Wind Shear Using Artificial Neural Networks”. *AIAA Guidance, Navigation, and Control (GNC) Conference*. 2013.
20. J. Sebes, W. Vanskike, M. Williams, S. McCandless, **T. Stastny**, G. Worden, N. Brunkhorst. “Flight Testing and Evaluation of the Structural Response to Flight Loads of a Small Scale Unmanned Aerial System”. *AIAA Infotech@ Aerospace*. 2012.
21. W. Vanskike, M. Williams, **T. Stastny**, A. Ghatte, S. McCandless, T. Peckman. “Hawkeye UAV Dynamic Analysis”. *AIAA Modeling and Simulation Technologies Conference*. 2011.

Magazine Articles

1. **T. Stastny**. “Mars Exploration? Unleash the Swarms!”. *Ruimtevaart*. 2013.

Patents

1. M. Arigoni, R. Simpson, S. Fuhrer, P. Beardsley, D. Mammolo, M. Burri, M. Bischoff, **T. Stastny**, L. Rodgers, D. Krummenacher, and R. Siegwart. “Vehicles Configured For Navigating Surface Transitions”. *US Patent 10,464,620*. 2019.

Manuscripts Under Review

Pre-prints of papers *under review* available on request.

1. D. Rohr, M. Studiger, **T. Stastny**, N. Lawrance, and R. Siegwart. “Nonlinear Model Predictive Velocity Control of a VTOL Tiltwing UAV”. *IEEE Robotics and Automation Letters (RA-L)*.
2. F. Rockenbauer, S. Jeger, L. Beltran, M. Berger, M. Harms, N. Kaufmann, M. Rauch, M. Reinders, N. Lawrance, **T. Stastny**, R. Siegwart. “Dipper: A Dynamically Transitioning Aerial-Aquatic Unmanned Vehicle”. *Robotics Science and Systems (RSS)*.

Manuscripts in Preparation

Drafts of papers *in preparation* available on request.

1. **T. Stastny**, T. Hinzmann, D. Rohr, and R. Siegwart. “Vision-Based, Terrain-Aware Local Re-Planning for Low-Flying Fixed-Wing UAVs using Nonlinear MPC”. *Journal of Field Robotics (JFR)*.
2. **T. Stastny** and R. Siegwart. “Stability and Robustness Analysis of Efficient, Wind-Aware Nonlinear Guidance for Small Fixed-Wing UAVs”. *IEEE Transactions on Control Systems Technology*.
3. G. Heinrich, S. Vogt, **T. Stastny**, N. Lawrance, and R. Siegwart. “Design and Analysis of Span and Chord-Wise Wing-Fitted Pressure Sensors for In-Flight Post-Stall Airflow Characterization of a Fixed-Wing UAV”. *AIAA Journal of Guidance, Control, and Dynamics*.

- 2019 **Monitoring Glaciers Beyond the Horizon**
T. Stastny. Workshop on Informed Scientific Sampling in Large-scale Outdoor Environments. *International Conference on Robots and Intelligent Systems (IROS)*. . <https://scientific-sampling-robots.github.io/iros-2019-workshop/>
- 2018 **Towards Fully Autonomous Long-range Remote Sensing via Solar-powered Fixed-wing Unmanned Aerial Vehicles**
T. Stastny. Application of Unmanned Aerial Systems. *WSL Applied Remote Sensing Lectures*. Davos, Switzerland.
- 2018 **Multi-hour Autonomous Monitoring of Arctic Glaciers with Solar-Powered UAVs**
T. Stastny. Autonomous Navigation for Aerial Robots in Extreme Environments: From Subterranean Environments to the Arctic. *International Conference on Unmanned Aerial Systems (ICUAS)*. Dallas, TX, USA.
- 2017 **Monitoring Calving Glaciers in the Arctic via Solar-Powered UAVs**
T. Stastny. UAVs for Agricultural and Multispectral Remote Sensing. *International Conference on Unmanned Aerial Vehicles in Geomatics (UAV-G)*. Bonn, Germany.
- 2017 **From Guidance to Local Planning: Applying NMPC to Small, Fixed-Wing UAVs**
T. Stastny. IfA Coffee Talk. *Automatic Control Laboratory (IfA), ETH Zürich*. Zürich, Switzerland.
- 2015 **Adventura AtlantikSolar@Brazil**
T. Stastny, T. Hinzmann, P. Oettershagen. *Drone Show Latin America*. São Paulo, Brazil.