



Krock-2 Amphibious Quadruped

Krock 2 is a sprawling-gait quadrupedal robot developed under the NCCR Robotics grant, aimed at investigating locomotion through cluttered and wet terrain in search and rescue scenarios. The robot is capable of terrestrial locomotion as well as aquatic gaits along the surface of water when equipped with its tailored dry suit. The robot was developed by Kamilo Melo and Tomislav Horvat and is currently maintained by Matt Estrada <matthew.estrada@epfl.ch>

Key Features

- thermal and a wide-angled camera
- 21 Dynamixel motors
- two ODROID XU4 computers
- VectorNav IMU
- Waterproof suit

Possible Applications

- Search&Rescue
- Studying terrain/water locomotion



Access information

Corresponding infrastructure	École Polytechnique Fédérale de Lausanne BioRobotics Lab
Location	Route Cantonale, 1015 Lausanne, Switzerland
Unit of access	Working day

Technical specifications

DoF	21
Interface	Joystick controller, ROS interface
Power supply	16V LiPo battery
Weight	4.5 kg
Length	1 m

Additional information

<https://gitlab.com/biorob-krock/krock-controller>