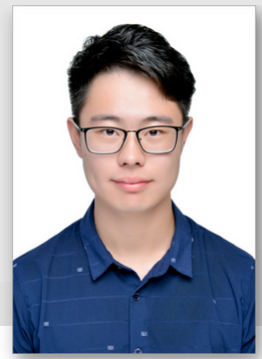


# Chenhao Li

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## EDUCATION

<b>ETH Zurich, Zurich, Switzerland</b>	09.2020 - current
Master's Degree in Robotics, Systems and Control, 5.95 / 6.0	
<b>Tongji University, Shanghai, China</b>	09.2015 - 07.2020
Bachelor's Degree in Mechanical Engineering, 4.93 / 5.0	Excellent Graduate

## WORK EXPERIENCE

<b>Visiting Researcher, Massachusetts Institute of Technology, United States</b>	01.2023 - current
<ul style="list-style-type: none"><li>Self-supervised structured robot dynamics learning.</li><li>Intelligent adaptive curriculum learning in continuous task space.</li></ul>	
<b>Research Intern, Max Planck Institute for Intelligent Systems, Germany</b>	04.2022 - 12.2022
<ul style="list-style-type: none"><li>Agile robot skill development with generative adversarial imitation learning (AMP, WASABI).</li><li>Intrinsic skill diversification through mutual information maximization (DIAYN, DADS, DISDAIN, CASSI).</li><li>Morphology-inspired robot learning with graph neural networks (GCN, NerveNet).</li></ul>	

## PUBLICATIONS

<b><u>Versatile Skill Control via Self-supervised Imitation of Unlabeled Mixed Motions</u></b>	ICRA 2023
<i>Chenhao Li, Sebastian Blaes, Pavel Kolev, Marin Vlastelica, Jonas Frey, Georg Martius</i>	
<ul style="list-style-type: none"><li>Cooperative Adversarial Self-supervised Skill Imitation (CASSI): an adversarial imitation approach with unsupervised skill discovery techniques for obtaining controllable skill sets from unlabeled datasets containing diverse state transition patterns by discriminability maximization.</li></ul>	
<b><u>Learning Agile Skills via Adversarial Imitation of Rough Partial Demonstrations</u></b>	CoRL 2022 oral
<i>Chenhao Li, Marin Vlastelica, Sebastian Blaes, Jonas Frey, Felix Grimmeringer, Georg Martius</i>	<b>best paper finalist</b>
<ul style="list-style-type: none"><li>Wasserstein Adversarial Behavior Imitation (WASABI): a generative adversarial method for inferring reward functions from partial and potentially physically incompatible demonstrations for agile skill acquirement where reference or expert demonstrations are not easily accessible.</li></ul>	

## INVITED TALKS

<b>Biomimetic Robotics Lab</b> , Massachusetts Institute of Technology, United States	01.2023
<b>Machines in Motion Laboratory</b> , New York University, United States	12.2022
<b>Robotic Systems Lab</b> , ETH Zurich, Switzerland	08.2022

## REVIEWER SERVICE

<b>International Conference on Intelligent Robots and Systems (IROS)</b>	2023
<b>Conference on Robot Learning (CoRL)</b>	2023

## AWARDS

<b>ETH AI Center Doctoral Fellowship (1%)</b>	03.2023
<b>Best Paper Award Finalist (CoRL 2022)</b>	12.2022
<b>ETH Scholarship</b>	02.2022, 02.2023
<b>National Scholarship (0.2%)</b>	11.2018, 11.2016