PIETRO GRIFFA
Robotics Engineer

CONTACT

- Winterthurerstrasse 101
  8006 Zurich
- +41 0762429484
- griffap@student.ethz.ch
- pietrogriffa.github.io
- github.com/PietroGriffa

EDUCATION

2018 - Present

Master of Science
Robotics, Systems and Control
ETH Zurich

2015 - 2018

Bachelor of Science
Mechanical Engineering
Politecnico Milano

SKILLS

Python | Deep Learning | Docker
Linux | MATLAB | ROS | C
Embedded Systems

LANGUAGE

Italian *mothertogue*

English *advanced*

Deutsch *basic*

PROFILE

Born in January 1997 in Milano, I'm currently a Master Student at ETH Zurich. I have a passion for Robotics and related technologies, such as Computer Vision and Deep Learning, enriching my professional background with intense readings about human behaviours and management. I love cooperating in heterogeneous, dynamic, and highly-motivated teams, to which I can offer my best qualities, challenging others and myself for continuous improvements. I have an international experience gained in practice and studies, an orientation to problem solving, and a strong attitude to flexibility and creative thinking.

EXPERIENCE

Duckietown, *Teaching Assistant* Feb 20 - Present
- Zurich, Switzerland

Teaching Assistant at ETH Zurich for Duckietown. Developed new functionalities for the platform, and was as part of the team organizing the 5th edition of AI-DO in conjunction with NeurIPS 2020.

PERCRO, *Visiting Researcher* Sep 18 - Jan 19
- Pisa, Italy

Worked with the PERCeptual RObotics lab at Sant'Anna di Pisa to design and prototype a novel end-effector for tele-ultrasonography.

OOI Optimized Oilfield, *Intern* Aug 17 - Oct 17
- Calgary, Canada

Working side by side with the Company CEO, I experienced managing a company and designing new products in the area of casing gas compressors.

Aspen Tech, *Intern* Aug 16 - Oct 16
- Houston, Texas

Development of customized demos of the Company software solution, for complex systems predictive maintenance, mainly for the oil&gas market.

PROJECTS

Tactile Enabled Robotic Grasping
Superisors: Carlo Sferrazza
Development of novel grasping policies and applications leveraging the integration of an innovative vision-based tactile sensor with a state of the art robotic system.

Object-aware Active 3D Perception
Superisors: Margarita Grinvald, Julian Förster
Design of a novel object-aware Next Best View planner for a multi-object scenario, to autonomously generate scanning trajectory for reconstructing high quality object-level maps efficiently.

Adaptive Lane Following
Superisors: Ph.D. Jacopo Tani
Design of an Adaptive Controller to calibrate on the fly a scaled autonomous vehicle. This was developed and tested on the Duckietown platform.
- github.com/duckietown-ethz/proj-lf-adaptive

Kinematic optimization of an end-effector for tele-ultrasonography
Supervisors: Ph.D. Alessandro Filippeschi, Ph.D. Carlo Alberto Avizzano
Desing and kinematic optimization of an end-effector for a COTS robotic arm (UR5), to guarantee optimal functionality during tele-operated ultrasonography.
- **The International Conference of IFToMM ITALY, 2020**