Tunnel Disaster Response and Recovery Challenge
REL-UoA-JAEA　[Japan]
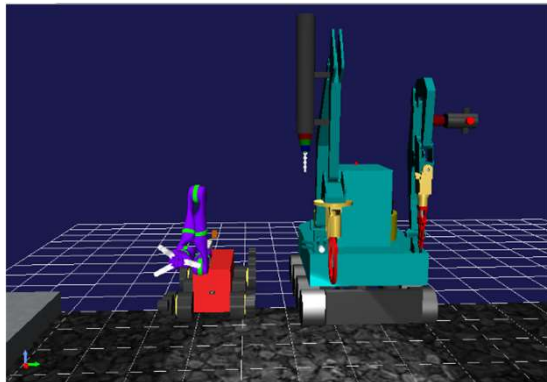
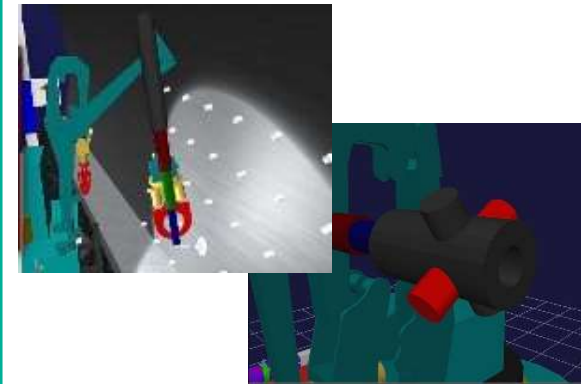## Development point

We implemented 'end-scope' and 'extracting-tool' models for "enryu". The end-scope moves up and down with stretch function useful for detailed and wider area inspection. QR code reading program will help end-scope inspection. The extracting-tool enables stable operation to rotate and to pull out the stick.


Introduction of your team

【Inspiration, motivation to form a team 】 Our seniors in the university invited us to join the WRS team. We think simulation technology, with which robotics development can be done safely and in-expensively in virtual space, is valuable to be familiar with.

【Future outlook】 Based on the knowledge and technology we get through WRS competition, we will use simulation by modeling the real world in the virtual space like CPS, and develop new software. The result will be verified in physical space. By iterating the cycle, it will be implemented on our real robot.

Role	Name	Affiliation/Title	Specialty, Field of study
	WATANOBE Yutaka	The University of Aizu, Senior Associate Professor	Software Engineering, Cloud Robotics, Smart Learning
Team leader	AOBA Ryuma	The University of Aizu, 4th year student	Attitude Control, Data Communication
	OHASHI Ayato	The University of Aizu, 4th year student	Image Processing
	TSURUNO Kota	The University of Aizu, 4th year student	Attitude Control
	Kabir RAIHAN	The University of Aizu, 1st year master	Cloud Robotics, Machine Learning, Image Processing
	SHIGA Mizuki	The University of Aizu, 3rd year student	Attitude Control
	OGATA Shunsuke	The University of Aizu, 3rd year student	Attitude Control, Programming
	ANAZAWA Tsuyoshi	FSK Co., Ltd.	Robotics simulation
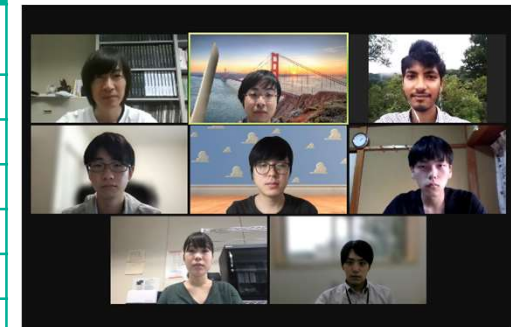
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