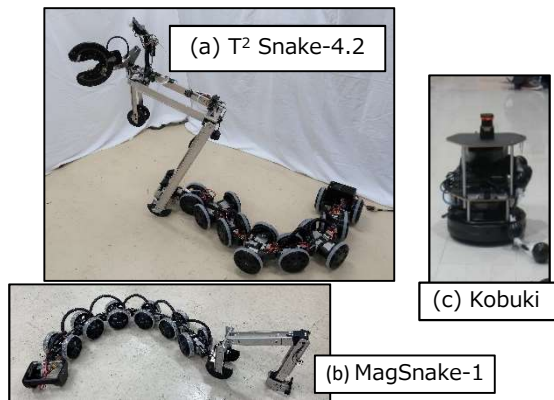
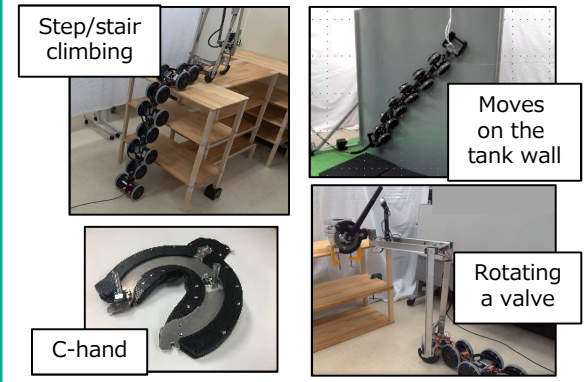


# UEC-Snake (Tokyo, Japan)



## Development point

- **T<sup>2</sup> Snake-4.2** enters narrow paths, climbs obstacles, climbs stairs, inspects gauges, and rotates a valve by "C-hand."
- **MagSnake-1** moves, climbs obstacles, and inspects on the tank wall.
- **Kobuki** inspects autonomously in cooperation with other robots.

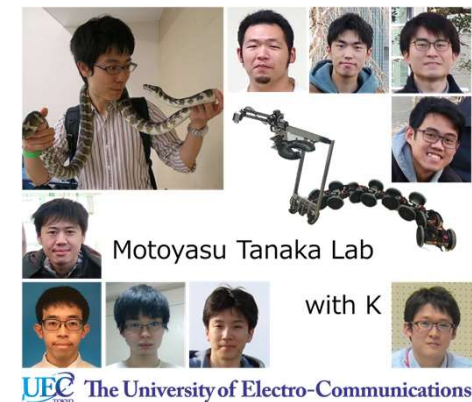


**Introduction of your team**

【Inspiration, motivation to form a team】  
 Our lab studies snake robots. Inspection in industrial plants is one of the applications of long slender snake robots. We aim to demonstrate the potential of snake robots in plant inspection.

【Future outlook】  
 We will continue our research and development of snake robots to solve the current issues and problems identified in this challenge.

Role	Name	Affiliation/Title	Specialty, Field of study
Team leader, control	Motoyasu Tanaka	The University of Electro-Communications (UEC), Professor	Control of Snake robots and its application
Development of Kobuki	Kazuyuki Kon	Individual	Autonomous mobile robot
Support of hardware	Mizuki Nakajima	UEC, Postdoctoral researcher	Snake robots, Mechanism
Support of system	Yuichiro Kimura	UEC, 2nd year's master	Autonomous mobile robot
Operator of MagSnake-1	Shotaro Ueno	UEC, 1st year's master	Mechanism and control of MagSnake-1
Operator of T2 Snake-4.2	Ching Wen Chin	UEC, 1st year's master	Mechanism and control of C-hand and T2 Snake-4.2
Interface	Koki Furuike	UEC, 1st year's master	Interface
Support	Yuki Ishikawa	UEC, 4 <sup>th</sup> year's undergraduate	Snake robots
Support	Haruki Tanihira	UEC, 4 <sup>th</sup> year's undergraduate	Snake robots
Support	Sota Miyamoto	UEC, 4 <sup>th</sup> year's undergraduate	Snake robots, Mechanism



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