



## 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](mailto: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



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## Access information

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

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## Technical specifications

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

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## Additional information

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