

Maurice Rahme

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Summary

- Robotist at Boston Dynamics experienced in Optimization & Learning based control
- Took Stretch from a prototype to a real product with >10 million customer boxes moved to date
- Experienced in motor characterization and real-time controls

Education

Northwestern University, M.Sc. in Robotics - GPA: 3.95/4.0 Sep 2020
The University of Edinburgh, B.Eng in Mechatronics - First Class, GPA: 4.0/4.0 Jun 2019

Experience

Staff Robotics Engineer, Boston Dynamics – Detroit, MI (Remote) Jan 2022 - Present

- Technical Leader on Stretch Motion Planning and mentor to 6 colleagues
- Implemented Hybrid ML/Optimal Control scheme to balance performance with robustness
- Created novel methods for highly dextrous motion generation as seen at [MODEX](#)
- Increased Stretch's payload capacity from 15kg to 23kg using Wrench Minimization
- Enhanced handling of poorly supported cargo through sag-predictive collision avoidance
- Boosted Stretch trajectory speed by >2x

Senior Robotics Engineer, Boston Dynamics – Waltham, MA Nov 2020 - Jan 2022

- Designed robot manufacturing SW, enabling the production of >200 Stretch robots to date
- Created a custom dyno-style actuator characterization software suite for BLDC motors
- Implemented Directed Graph search library (A*, D*Lite)
- Wrote Task-Space Controller for Stretch Base Driving to prevent wheel motors from overheating

Publications / Patents

SYSTEMS AND METHODS FOR GRASPING OBJECTS WITH UNKNOWN OR UNCERTAIN EXTENTS USING A ROBOTIC MANIPULATOR - Patent: 20250135636 May 2025

Linear Policies are Sufficient to Enable Low-Cost Quadrupedal Robots to Traverse Rough Terrain - 10.1109/IROS51168.2021.9636011 Sep 2021

Projects

Spot Mini Mini

- Architected novel Reinforcement Learning method for Terrain Adaptation
- Designed, built, and open-sourced quadruped that can be made for under \$600

Motion Planning in C++

- Implemented scalable Probabilistic Roadmap and Grid Map
- Developed Library containing A*, Theta*, D*Lite, Potential Fields, MPPI

Skills

Languages/Libraries: C++, Python, Eigen, Pytorch, Einops, Pandas, Isaac, ROS, Genesis, Gazebo, W&B

Technical: Optimal Control, Machine Learning, Dexterous Manipulation, Motor Characterization, State Estimation