IMAV 2026

17th International Micro Air Vehicle Conference and Competition

September 21-25, 2026

Strasbourg, France

www.imavs.org

Contents

IMAV2026 1
Preface . . . 3
International IMAV Committee . . . 4
Organizing Committee . . . 4
Reviewers . . . 4
Sponsors . . . 5
Call for Papers . . . 6
Sessions . . . 7
Keynote Speakers . . . 8
List Of Papers . . . 11
Authors . . . 12

Papers 14
Rapid Sim-to-Real Reinforcement Learning for Autonomous Drone Racing . . . 15
Precision Home Landing for Bee-Nav Robot Navigation . . . 23
VLN on the Fly: An Onboard Vision-Language Navigation Stack for Aerial Robots . . . 31
MRAC-Based Admittance Control for Aerial Physical Interaction . . . 38
Variable Admittance Control for Obstacle Separation in Aerial Manipulation . . . 46
Online Wind Field Estimation for Airborne Wind Energy Systems in Circular Flight . . . 54
Sequential Estimation of Fixed-Wing UAV Aerodynamic Coefficients: Evaluation on Pitch/Roll Flight Da . . . 62
TriMorph: The Transformative Tricopter . . . 70
Weitflug: A Research-Oriented Fork of Betaflight for Agile Autonomous Flight . . . 77
Flight-Ready LiDAR-Inertial Odometry for Embedded Drone Platforms . . . 84
LiDARFlow: Real-Time Panel-Based MAV Guidance in Unknown Environments . . . 91
Monocular Geo-Localization of Terrestrial Objects from UAV Imagery with Spatial Refinement . . . 99
Actuator Nonlinear Fault-Tolerant Control of a Fast-Spinning Quadrotor with Loss of Two Opposing Rot . . . 107
AERO-LQG: Aerial-Enabled Robust Optimization for LQG-Based Quadrotor Flight Controller . . . 117
Parameter Sensitivity in Control Allocation: A Monte Carlo Analysis for an Over-Actuated Aerial Robo . . . 125
Aerodynamic Investigation of Fan-in-Wing Propulsion at Low Reynolds Numbers for Micro Aerial Vehicle . . . 133
A Multi-View, Multi-LiDAR Synchronised Setup for Smoke Plume Data Acquisition: A Simulated Drone Swa . . . 141
Vision-guided Velocity Control of Micro Air Vehicles using Rate-decoded Spiking Neural Network . . . 149
Decentralized PSO-Based Guidance for Multi-UAV Wildfire Monitoring and Frontier Tracking . . . 157
Distributed Formation Control based on Bounded Voronoi and Cable Tension for Cooperative Hovering of . . . 165
A Structure-Aware Reactive Motion Planner for Autonomous Nano-UAV Navigation in Confined 3D Tunnels . . . 173
Downscaling Autonomous Navigation of Tiny Drones under Dense Forest Canopies . . . 180
Safe Synchronous Path Planning for a Fleet of Fixed-Wing Constant Speed Aircraft . . . 188
Center-of-Gravity Placement Effects on a Bio-Inspired Flapping-Wing MAV: An Empirical Characterizati . . . 196
Pitch Stabilisation and Longitudinal Control of a Hummingbird-Inspired Drone Using an Active Tail . . . 202
Experimental Identification of the Yaw Damping Derivative of a Flapping-Wing Micro Air Vehicle . . . 210

Preface

On behalf of the Local Organizing Committee, it is our pleasure to present the proceedings of the 17^{th} International Micro Air Vehicle Conference and Competition, which was held in Strasbourg, France from September 21-25, 2026. Organized in coordination with the SIS67 fire department and the 2nd Hussard Regiment, this edition focused on managing rescue operations in fire conditions. We extend our warm thanks to all sponsors and organizers for making the event possible.

These proceedings are available to the public as open-access publications, seeking to promote and contribute to the advancement of the state-of-the-art in the area of small flying robots and their applications for the benefit of society.

The IMAV is a pioneering scientific-technological event in the field of aerial robotics and has been established as the primary event for the communities of researchers dedicated to the study, development, and research of Micro Air Vehicles. By participating in authentic competition scenarios, encompassing indoor and outdoor environments, as well as presenting innovative solutions via conference papers, the boundaries of research in the field of Micro Air Vehicles (MAVs) are continuously pushed forward.

These proceedings contain twenty-six peer-reviewed scientific papers by eighty-eight authors organized in nine sessions presented at the IMAV in 2026. The topics of these papers contain a nice mix ranging from aerial vehicle design and energy sources to control, navigation and perception. Together, the papers give an overview of the current state-of-the-art in the field of Micro Air Vehicles.

We would like to express our sincere gratitude for the guidance and support of the nineteen members of the International Committee from fifteen institutes, who guide IMAV overall. In addition to the presentation of the scientific papers, keynote talks were delivered by experts in the field, whom we want to thank for their valuable contributions. We also want to thank the five members of the Local Organizing Committee for their invaluable support in the organization of this IMAV-2026.

Strasbourg, France. September 2026

Renaud Kiefer
General Chair
INSA
email: imav2026@insa-strasbourg.fr

International IMAV Committee

Bart Remes . . . . . TUDelft, Delft, the Netherlands
Ben M. Chen . . . . . CUHK, Hong-Kong, China
Christophe De Wagter . . . . TUDelft, Delft, the Netherlands
Dieter Moormann . . . . . RWTH, Aachen, Germany
Gautier Hattenberger . . . . . ENAC, Toulouse, France
Guido de Croon . . . . . TUDelft, Delft, the Netherlands
Hector J. Garcia de Marina Peinado . . UCM, Madrid, Spain
Jean-Marc Moschetta . . . . . ISAE, Toulouse, France
José Martinez-Carranza . . . . . INAOE, Puebla, Mexico
Karl Stol . . . . . UOA, Auckland, New Zealand
Leandro Lustosa . . . . . ISAE-SUPAERO, Toulouse, France
Marcelo Becker . . . . . USP, São Paulo, Brazil
Mohamed Abdulghani . . . . . RMIT, Melbourne, Australia
Murat Bronz . . . . . ENAC, Toulouse, France
Pascual Campoy . . . . . UPM, Madrid, Spain
Renaud Kiefer . . . . . INSA, Strasbourg, France
Simon Watkins . . . . . RMIT, Melbourne, Australia
Thipyopas Chinnapat . . . . . KU, Bangkok, Thailand
Tom Richardson . . . . . UOB, Bristol, UK

Organizing Committee

Renaud Kiefer . . . . . INSA, , General Chair
Sylvain Durand . . . . . INSA, , Conference Chair
Caio Fonseca . . . . . INSA, , Indoor Competition Chairs
Thomas Pavot . . . . . INSA, , Outdoor Competition Chairs
Edouard Laroche . . . . . INSA, , Sponsors Chair

Reviewers

Abuali Saleh . . . . . , ,
Al-Zubaidi Salim . . . . . , ,
Alkimim Dos Santos Lívia . . . . . , ,
Arias-Perez Pedro . . . . . , ,
Arnous Asil . . . . . , ,
Asignacion Abner . . . . . , ,
Bara Iulia . . . . . , ,
Batista Bruno . . . . . , ,
Borne Augustin . . . . . , ,
Chakraa Hamza . . . . . , ,
Chan Woei-Leong . . . . . , ,
Changey Sebastien . . . . . , ,
De Croon Guido . . . . . , ,
De Ponti Tomaso . . . . . , ,
De Wagter Christophe . . . . . , ,
Durand Sylvain . . . . . , ,
Engelsman Daniel . . . . . , ,
Fernandez Cortizas Miguel . . . . . , ,
Feurgard Maël . . . . . , ,
Fonseca De Freitas Caio . . . . . , ,
Gangloff Jacques . . . . . , ,
Gaona Alvaro . . . . . , ,
Garreau Aurélien . . . . . , ,
Gonzalez Silva Eduardo . . . . . , ,
Gp-Lenza Guillermo . . . . . , ,
Guerrero-Castellanos Fermi . . . . . , ,
Hafez Ishaq . . . . . , ,
Harzer Jakob . . . . . , ,
Hattenberger Gautier . . . . . , ,
Kempf Aurélie . . . . . , ,
Klimont Joel . . . . . , ,
Labhade Jayant Kailas . . . . . , ,
Laroche Edouard . . . . . , ,
Lebreton Clément . . . . . , ,
Machado Joao . . . . . , ,
Melis Arno . . . . . , ,
Melo Joao . . . . . , ,
Mendoza-Robles Natalio . . . . . , ,
Moschetta Jean-Marc . . . . . , ,
Ou Dequan . . . . . , ,
Pavot Thomas . . . . . , ,
Peng Yufei . . . . . , ,
Pivert Maya . . . . . , ,
Pouthier Florian . . . . . , ,
Pérez Rafael . . . . . , ,
Rey Thomas . . . . . , ,
Roussel Emmanuel . . . . . , ,
Saade Joya Maria . . . . . , ,
Saeed Burhan . . . . . , ,
Setayeshi Amirali . . . . . , ,
Smith Charles . . . . . , ,
Soprani Tayar Marco . . . . . , ,
Stol Karl . . . . . , ,
Viollet Stéphane . . . . . , ,
Watkins Simon . . . . . , ,
Willinger-Adam Pierre . . . . . , ,
Xin Songyan . . . . . , ,
Xolo-Tlapanco Nilda G. . . . . , ,
Yigit Arda . . . . . , ,
Youbi Lounès . . . . . , ,
Zwanenburg Andreas . . . . . , ,

Organizers

IMAV-2026 was organized in coordination with the SIS67 fire department and the 2nd Hussard Regiment. This edition focused on managing rescue operations in fire conditions.

SAPEURS-POMPIERS du BAS-RHIN

https://www.sis67.alsace/

2eme Regiment de Hussards

Sponsors

IMAV-2026 was made possible thanks to the great support of:

INSA INSTITUT NATIONAL DES SCIENCES APPLIQUÉES STRASBOURG

https://www.insa-strasbourg.fr/

FRANCE 2030

https://www.france2030.gouv.fr

iCUBE

https://icube.unistra.fr/

University of Strasbourg

https://www.unistra.fr/

DELAIR AERIAL INTELLIGENCE

https://delair.aero/

Dronisos

https://www.dronisos.com/

Call for Papers

About IMAV

The international Micro Air Vehicle Conference and Competition (IMAV) is an annual event combining cutting-edge research and drone competitions. It features keynote talks by renowned experts and peer-reviewed paper presentations.

This year's edition will take place at the Institut National des Sciences Appliquées de Strasbourg (INSA Strasbourg), in Strasbourg, Bas-Rhin, France, on September 21st - 25th, 2026.

IMPORTANT DATES

PAPER SUBMISSION DEADLINE
May 15, 2026

NOTIFICATION OF ACCEPTANCE
June 12, 2026

FINAL PAPER SUBMISSION
July 3, 2026

CONFERENCE TOPICS

- Low Reynolds number aerodynamics
- Unsteady aerodynamics
- Propulsion set and new energy sources
- Smart morphing materials
- Autonomous Drone Racing
- Autonomous navigation
- Control theory and state estimation
- Cooperation and formation flight
- Sense & avoid integration of UAVs in airspace
- Computer vision for MAVs
- Reconfiguration in unpredicted events
- New MAV architectures
- Characterization of noise emission for MAVs
- Low noise and noise mitigation

For all inquiries, please contact: imav2026@insa-strasbourg.fr

Organised by:

INSA Institut National des Sciences Appliquées Strasbourg

iCUBE

Université de Strasbourg

In coordination with:

Sapeurs-Pompiers du Bas-Rhin

Website

2026.imavs.org

http://www.imavs.org/

Conference Oral Presentations

Session 1: Learning and Adaptive Systems

Rapid Sim-to-Real Reinforcement Learning for Autonomous Drone Racing p.15
Precision Home Landing for Bee-Nav Robot Navigation p.23
VLN on the Fly: An Onboard Vision-Language Navigation Stack for Aerial Robots p.31

Session 2: Admittance Control and Aerial Interaction

MRAC-Based Admittance Control for Aerial Physical Interaction p.38
Variable Admittance Control for Obstacle Separation in Aerial Manipulation p.46
Online Wind Field Estimation for Airborne Wind Energy Systems in Circular Flight p.54
Sequential Estimation of Fixed-Wing UAV Aerodynamic Coefficients: Evaluation on Pitch/Roll Flight Da... . . . . p.62

Session 3: Innovative Architectures and Software Tools

TriMorph: The Transformative Tricopter p.70
Weitflug: A Research-Oriented Fork of Betaflight for Agile Autonomous Flight p.77

Session 4: Advanced LiDAR and Vision for Autonomous Navigation

Flight-Ready LiDAR-Inertial Odometry for Embedded Drone Platforms p.84
LiDARFlow: Real-Time Panel-Based MAV Guidance in Unknown Environments p.91
Monocular Geo-Localization of Terrestrial Objects from UAV Imagery with Spatial Refinement p.99

Session 5: Robust Control and Fault Tolerance

Actuator Nonlinear Fault-Tolerant Control of a Fast-Spinning Quadrotor with Loss of Two Opposing Rot... . . . . p.107
AERO-LQG: Aerial-Enabled Robust Optimization for LQG-Based Quadrotor Flight Controller p.117
Parameter Sensitivity in Control Allocation: A Monte Carlo Analysis for an Over-Actuated Aerial Robo... . . . . p.125

Session 6: Aerodynamics and Propulsion for MAVs

Aerodynamic Investigation of Fan-in-Wing Propulsion at Low Reynolds Numbers for Micro Aerial Vehicle... . . . . p.133

Session 7: Swarm Guidance and Multi-Sensor Perception

A Multi-View, Multi-LiDAR Synchronised Setup for Smoke Plume Data Acquisition: A Simulated Drone Swa... . . . p.141
Vision-guided Velocity Control of Micro Air Vehicles using Rate-decoded Spiking Neural Network p.149
Decentralized PSO-Based Guidance for Multi-UAV Wildfire Monitoring and Frontier Tracking p.157
Distributed Formation Control based on Bounded Voronoi and Cable Tension for Cooperative Hovering of... . . . . p.165

Session 8: Navigation in Complex Environments

A Structure-Aware Reactive Motion Planner for Autonomous Nano-UAV Navigation in Confined 3D Tunnels p.173
Downscaling Autonomous Navigation of Tiny Drones under Dense Forest Canopies p.180
Safe Synchronous Path Planning for a Fleet of Fixed-Wing Constant Speed Aircraft p.188

Session 9: Bio-Inspired MAVs: Design and Control

Center-of-Gravity Placement Effects on a Bio-Inspired Flapping-Wing MAV: An Empirical Characterizati... . . . . p.196
Pitch Stabilisation and Longitudinal Control of a Hummingbird-Inspired Drone Using an Active Tail p.202
Experimental Identification of the Yaw Damping Derivative of a Flapping-Wing Micro Air Vehicle p.210

Keynote Speakers

Aerial Robotic Cable-Based Manipulation: Advancements and Emergent Challenges

Prof. Chiara Gabellieri – Assistant Professor in the Robotics and Mechatronics group of the EEMCS Faculty at the University of Twente, the Netherlands

Abstract

New research directions are emerging in both aerial manipulation of cable-suspended objects and the control of deformable cables with aerial robots, calling for novel modeling and control approaches. Beyond the well-studied problem of controlling cable-suspended loads with multirotor UAVs, recent work—primarily motivated by endurance limitations—is exploring manipulation using non-stop aerial vehicles. This paradigm introduces the challenge of achieving accurate control of the load pose while maintaining continuous motion of the carriers. Moreover, traditional cable models become insufficient when highly dynamic tasks are considered or where the cable itself becomes the deformable object to be shaped and controlled. Developments in this direction enables applications ranging from highly dynamic pick-and-place of slung loads to the collection of floating debris in waterways.

Counter-UAS Challenges and Research Perspectives: Building Sustainable and Adaptive Defense Architectures

Laurent Barrilliet – Program Director at ONERA[1], Versailles, France

Abstract

The rapid proliferation of low-cost, easily accessible drones has transformed the security and defense landscape. Recent conflicts have demonstrated how unmanned systems can provide air superiority and long-range strike capabilities at a fraction of the cost of conventional military assets. This asymmetry creates major challenges for Counter-UAS (C-UAS) systems, which must remain effective, sustainable, and scalable against evolving threats.

Designing efficient C-UAS architectures requires a comprehensive understanding of drone technologies, their potential evolution, and their impact on detection, information management, and neutralization capabilities. These architectures must also operate in contested environments characterized by GNSS denial, electronic warfare, operational constraints, and regulatory requirements.

Drawing on ONERA's expertise, instrumented drone fleet, test facilities, and multidisciplinary research laboratories, this presentation reviews key drone threat trends, associated risks, and ongoing research efforts aimed at reducing vulnerabilities. Operational examples, including the DIAMOND drone-track fusion algorithm and the SAP system deployed during the Paris 2024 Olympic Games, illustrate the transition from research to fielded capabilities.

[1]The French Aerospace Lab ONERA is a leading research organization dedicated to aerospace, defense, and space technologies

Centimeter-level precision for a large-scale pointillist artwork created by a drone (a world first)

Prof. Jacques Gangloff – Professor at Strasbourg University, France

Abstract

The highlight of the ANR "STRAD" (STReet Art Drone) project was the autonomous creation in July 2025 of a 5 m x 15 m outdoor mural by an aerial manipulator with centimeter-level precision. A world first. This achievement is the result of a four-year collaboration by a unique consortium comprising the ICube laboratory in Strasbourg, the Gipsa-lab in Grenoble, the company Polyvionics in Paris, and the Spacejunk association in Grenoble, which organizes Europe's largest street art festival, the "Street Art Fest Grenoble Alpes." This presentation will tell the story of this unique project at the intersection of science and art, from its inception to the completion of the final mural as part of the Street Art Fest 2025.

The quest for never-landing drones. From hydrogen to wind gradients

Prof. Jean-Marc Moschetta – Professor of Aerodynamics at ISAE-SUPAERO, Toulouse, France

Abstract

Fixed-wing drones powered by an electric motor can only achieve limited flight times due to the intrinsically low energy density of current Lithium batteries. On-board hydrogen can dramatically extend flight times if properly combined with efficiently designed fuel cells. Moreover, the use of cryogenic hydrogen can allow for even higher energy density if the airplane's consumption is properly adapted to the tank's natural boil-off rate. While crossing the Atlantic Ocean (3000 km) with an electric fixed-wing aircraft equipped with Lithium cells is impossible at any take-off weight, that task is feasible for a liquid hydrogen-powered drone of less than 15 kg. In addition to that, taking advantage of wind gradients could further extend the maximum range of drones with the objective of staying airborne for several days. The presentation will finally discuss the use of a Lidar Doppler in view of take advantage of atmospheric disturbances.

Building long-range aerial sensors (Defense and industrial applications, since 2011)

Bastien Mancini – CEO of DELAIR[2], Toulouse, France

Abstract

Delair was founded in 2011 by Michaël de Lagarde, Benjamin Benharrosh, Benjamin Michel, and Bastien Mancini, and quickly became a pioneer in professional UAV systems. In 2012, its DT18 became the first drone certified in France for BVLOS (Beyond Visual Line of Sight) operations, marking a major milestone for the company and the industry.

Over the years, Delair expanded through strategic acquisitions and partnerships, including Airware (and its subsidiary Redbird), Gatewing from Trimble, and collaborations with Intel and international distributors. The company also supplied drones for defense and surveillance applications, notably in Ukraine, and strengthened its presence in both civilian and military markets.

More recently, Delair has become a key actor in European defense drone programs, working with partners such as KNDS and MBDA on loitering munitions and tactical UAVs. Its systems, including the DT-46 and new hybrid platforms, are now used by French armed forces and other security actors, reflecting its shift toward high-performance dual-use technologies and autonomous systems.

Implementing Ultra-Wideband (UWB) Technology in Robot Swarms

Rémi Potet & Antoine Potet – Chief Technology Officers of Dronisos[3], Bordeaux, France

Abstract

This presentation examines the integration of Ultra-Wideband (UWB) technology within robot swarms, outlining its operational capabilities and the technical phases of implementation. The keynote will address the following key areas:

- Dynamic Infrastructure: An analysis of the operational viability and implications of using moving or flying anchors instead of static reference points.
- UWB Capabilities: An overview of UWB performance specifications for multi-agent coordination.
- Positioning Techniques: An evaluation of standard UWB localization architectures, specifically RTDOA, TDOA, and TWR.
- Technical Challenges: A review of obstacles in real-world deployment, focusing on clock synchronization, multipath mitigation, time-slot allocation, and error characterization in sensor fusion.

[2]French company that designs and manufactures professional fixed-wing drones and data solutions for industrial inspection, surveying, and defense applications

[3]French company specializing in autonomous drone light shows, developing swarm technologies and large-scale aerial entertainment solutions for events worldwide

Papers

[1] Rapid Sim-to-Real Reinforcement Learning for Autonomous Drone Racing p.15
[2] Precision Home Landing for Bee-Nav Robot Navigation p.23
[3] VLN on the Fly: An Onboard Vision-Language Navigation Stack for Aerial Robots p.31
[4] MRAC-Based Admittance Control for Aerial Physical Interaction p.38
[5] Variable Admittance Control for Obstacle Separation in Aerial Manipulation p.46
[6] Online Wind Field Estimation for Airborne Wind Energy Systems in Circular Flight p.54
[7] Sequential Estimation of Fixed-Wing UAV Aerodynamic Coefficients: Evaluation on Pitch/Roll Flight Da p.62
[8] TriMorph: The Transformative Tricopter p.70
[9] Weitflug: A Research-Oriented Fork of Betaflight for Agile Autonomous Flight p.77
[10] Flight-Ready LiDAR-Inertial Odometry for Embedded Drone Platforms p.84
[11] LiDARFlow: Real-Time Panel-Based MAV Guidance in Unknown Environments p.91
[12] Monocular Geo-Localization of Terrestrial Objects from UAV Imagery with Spatial Refinement p.99
[13] Actuator Nonlinear Fault-Tolerant Control of a Fast-Spinning Quadrotor with Loss of Two Opposing Rot p.107
[14] AERO-LQG: Aerial-Enabled Robust Optimization for LQG-Based Quadrotor Flight Controller p.117
[15] Parameter Sensitivity in Control Allocation: A Monte Carlo Analysis for an Over-Actuated Aerial Robo p.125
[16] Aerodynamic Investigation of Fan-in-Wing Propulsion at Low Reynolds Numbers for Micro Aerial Vehicle p.133
[17] A Multi-View, Multi-LiDAR Synchronised Setup for Smoke Plume Data Acquisition: A Simulated Drone Swa . p.141
[18] Vision-guided Velocity Control of Micro Air Vehicles using Rate-decoded Spiking Neural Network p.149
[19] Decentralized PSO-Based Guidance for Multi-UAV Wildfire Monitoring and Frontier Tracking p.157
[20] Distributed Formation Control based on Bounded Voronoi and Cable Tension for Cooperative Hovering of p.165
[21] A Structure-Aware Reactive Motion Planner for Autonomous Nano-UAV Navigation in Confined 3D Tunnels . p.173
[22] Downscaling Autonomous Navigation of Tiny Drones under Dense Forest Canopies p.180
[23] Safe Synchronous Path Planning for a Fleet of Fixed-Wing Constant Speed Aircraft p.188
[24] Center-of-Gravity Placement Effects on a Bio-Inspired Flapping-Wing MAV: An Empirical Characterizati p.196
[25] Pitch Stabilisation and Longitudinal Control of a Hummingbird-Inspired Drone Using an Active Tail p.202
[26] Experimental Identification of the Yaw Damping Derivative of a Flapping-Wing Micro Air Vehicle p.210

Authors

A

Abuali, Saleh p.165
Al-zubaidi, Salim p.125
Asignacion Jr, Abner p.173

B

Barros, Edna p.99
Becker, Marcelo p.31
Bello, Ivan Guerra p.196
Bilgin, Zeynep p.91
Briñón-Arranz, Lara p.165
Bronz, Murat p.91, p.141, p.157
Buchsteiner, Jakob p.15, p.77

C

Campoy, Francisco Anguita,Pascual p.84
Capezzuto, Gianluca p.31
Chakraa, Hamza p.141, p.157
Chan, Woei-Leong p.210
Croon, Guido de p.23
César, Pedro p.99

D

Delmas, Damien p.62
Denis, Lou p.141
Diehl, Moritz p.54
Durand, Nicolas p.188
Durand, Sylvain p.165

E

Eduardo, Bruno p.99
Engelsman, Daniel p.117

F

Farnault, Jules p.62
Ferreira, Mateus p.99
Feurgard, Maël p.157, p.188
Freitas, Pedro de p.31

G

Gallo, Mauro p.196
Gaona, Alvaro p.84
Godoy, Ricardo p.31
Grosu, Radu p.15, p.77

H

Hafez, Ishaq p.38, p.46
Hamaza, Salua p.180
Harzer, Jakob p.54
Hattenberger, Gautier p.188
Ho, Hann Woei p.149

I

Ingargiola, Jean-Marc p.70

K

Kempf, Aurélie p.62
Kido, Lucas p.31
Klein, Itzik p.117
Klimont, Joel p.15, p.77

L

Lacroix, Simon p.188
Lampalzer, Alexander p.15, p.77
Laroche, Edouard p.62
Lee, Jasper p.70
Li, Ni p.149
Liu, De-Jing p.210
Lopez, Austin p.196

M

Machado, João p.91
Mafalado, João Pedro p.99
Marchand, Nicolas p.165
Melis, Arno p.202
Melo, João p.99
Mendoza-Robles, Natalio p.165
Missinne, Quentin p.23
Moormann, Dieter p.54

O

Ou, Dequan p.23

P

Peng, Yufei p.149
Perez-Saura, David p.84
Ping, Burhan Saeed,Matthew Chong p.133
Pires, Driele p.99
Polkläser, Kim p.54
Ponti, Tomaso De p.107
Pérez, Gaétan p.141

R

Remes, Bart p.107
Renard, Felix p.54
Riquelme, Heitor p.99
Robu, Bogdan p.165
Roelandt, Thomas p.202
Rosa, Paulo p.99
Roussel, Emmanuel p.62

S

Saraiva, Pedro Antinio Rabelo p.31
Skinner, Jaap p.125
Smeur, Ewoud p.107
Sonego, Guilherme p.31
Souza, Pedro p.46
Stol, Karl p.38, p.46, p.125
Strub, Guillaume p.62
Suzuki, Satoshi p.173
Swevers, Jan p.202

T

Tayar, Marco p.31
Tommaselli, Felipe p.31

V

Vandepitte, Dirk p.202
Vanpoucke, Jeroen p.202
Verdoucq, Matthieu p.91
Viollet, Stéphane p.70

W

Wagter, Christophe De p.23

Z

Zwanenburg, Andreas p.180

Release

Draft
V1.0, Rev.16771M, 2026-09-23 15:10
Created by: Renaud Kiefer and C. De Wagter