

More than just building better learning algorithms for robots, I'm also interested in building hardware platforms to deploy these methods. Recently, I, with the help of my advisor, built a mobile manipulator, which is an arm manipulator fixed on a large wheeled robot, and is used for navigation and manipulation in both indoor and outdoor cluttered environments.

For my thesis, I only focus and work on two aspects related to Robot Control and Perception. First: developing distributed learning algorithms which can leverage knowledge from a large number of experiences/data obtained during training, using simulators or data collected by real-world robots. Second, tackling challenges which occur when this model/policy is deployed in a real-world robot using novel adaptation techniques.

With my knowledge of the practical aspects of Robot learning and perception, I can make some substantial contributions in applying some of the novel algorithms developed at Deepmind to real-world physical platforms. Deepmind has always been an ideal place to work for me. The collaborative culture in DeepMind allows me to learn from other researchers and contribute to the research based on my expertise.