Anukool Purohit

Deep Learning Engineer

✉ anukoolpurohit@gmail.com 📞 +91-7357223460 📍 A-44 Murlidhar Vyas Colony, Bikaner

↖ https://anukoolpurohit.github.io/

PROFESSIONAL EXPERIENCE

Sr. Deep Learning Engineer	02/2022 – present
Siterecon	Remote

Responsible for developing the training and inference infrastructure.
Improved model performance from 0.91 to 0.94 iou.
Reduced computational costs by 65%.

Software Engineer	09/2019 – 07/2021
Readink ∅	Remote

Helped develop the data labelling and curation tools.
Implementation of a functional k-means clustering engine in python.

Data Scientist	03/2016 – 04/2019
Kornea Digital ∅	Remote

Leverage data analytics to support customer development, marketing and product management for clients

EDUCATION

PhD Dropped out	09/2014 – 11/2015
University of Utah	Salt Lake City, Utah

B-tech Computer Science	09/2009 – 05/2013
BK Birla Institute of Enigineering and Technology, Rajathan Technical University	Pilani, India

COURSES

Deep Learning ∅	08/2021
Nueromatch Academy	

Computational Nueroscience	07/2021
Nueromatch Academy	

Deep Learning ∅	12/2018
DeepLearningAI	

PROJECTS

Decoding neural activity of handwriting planning in the motor cortex	08/2021
Nueromatch academy	

We hypothesised that since high dimensional neural activity in human brains can be represented by a small number of latent factors, these latent factors can be used to decode neural activity.
We extract latent factors in the neural data using LFADS, which were then used to predict the BCI output.

Investigating the role of the visual word form area during word recognition.	07/2021
Nueromatch academy	

Human performance of recognizing a word should degrade with higher word frequency
We hypothesized that this is due to the visual word form area in the brain failing to identify words that are moving too fast.
We test this hypothesis using FMRI data of a person performing word recognition tasks at different word frequencies. The frequency stimulus signal processed through a hemodynamic response function is encoded using a GLM. The resulting model shows that visual word form area response shows an inverted `U` shape change with increasing frequency.

Extending RRT algorithm for moving obstacles   12/2014
University of Utah
Built a simulated environment for a visual representation of the RRT algorithm in Matlab,
where some obstacles moved. At each step of the Path planning algorithm, we calculate the
new location of obstacles using a GMM.

EKF SLAM   12/2012
BKBKIET
Implemented EKF Slam in Matlab on a LegoMindstorm NXT, using its sonar sensor. The
Robot successfully navigated semi-structured environments.