

Beomjoon Kim

Contact Information	85 Hoegi-ro Dongdaemun-gu Seoul, Republic of Korea 02455	E-mail: beomjoon.kim@kaist.ac.kr http://https://beomjoonkim.github.io/
Education	<p><i>Ph.D. in Computer Science</i> Sept 2014 - May 2020 (Advisors: Leslie Pack Kaelbling and Tomás Lozano-Pérez) Massachusetts Institute of Technology, EECS, Cambridge, USA</p> <p><i>M.Sc. in Computer Science</i> Jan 2012 - Dec 2013 (Advisor: Joelle Pineau) McGill University, School of Computer Science, Montreal, Canada</p> <p><i>BMath. in Joint Honours of Computer Science and Statistics (with Distinction)</i> Sep 2007 - Dec 2011 University of Waterloo, Faculty of Mathematics, Waterloo, Canada</p>	
Journal Papers	<p>Representation, learning, and planning algorithms for geometric task and motion planning. Beomjoon Kim, Luke Shimanuki, Leslie Pack Kaelbling, Tomás Lozano-Pérez. <i>International Journal of Robotics Research (IJRR)</i>, 2021.</p> <p>Integrated task and motion planning. Caelan Reed Garrett, Rohan Chitnis, Rachel Holladay, Beomjoon Kim, Tom Silver, Leslie Pack Kaelbling, Tomás Lozano-Pérez. <i>Annual Review of Control, Robotics, and Autonomous Systems</i>, 2021.</p> <p>Learning to guide task and motion planning using score-space representation Beomjoon Kim, Zi Wang, Leslie P. Kaelbling, Tomás Lozano-Pérez. <i>International Journal of Robotics Research (IJRR)</i>, 2019.</p> <p>Socially adaptive path planning in dynamic environments using inverse reinforcement learning Beomjoon Kim, Joelle Pineau. <i>International Journal of Social Robotics</i>, 2015.</p>	
Selected Conference Papers	<p>A Long Horizon Planning Framework for Manipulating Rigid Pointcloud Objects. Anthony Simeonov, Yilun Du, Beomjoon Kim, Francois Hogan, Joshua Tenenbaum, Pulkit Agrawal, Alberto Rodriguez. <i>Conference on Robot Learning (CoRL)</i>, 2020. (Plenary talk. 12% acceptance rate)</p> <p>CAMPs: Learning Context-Specific Abstractions for Efficient Planning in Factored MDPs Rohan Chitnis*, Tom Silver*, Beomjoon Kim, Leslie Pack Kaelbling, Tomás Lozano-Pérez. <i>Conference on Robot Learning (CoRL)</i>, 2020. (Plenary talk. 12% acceptance rate)</p>	

Monte Carlo Tree Search in continuous spaces using Voronoi optimistic optimization with regret bounds

Beomjoon Kim, Kyungjae Lee, Sungbin Lim, Leslie P. Kaelbling, Tomás Lozano-Pérez.
AAAI Conference on Artificial Intelligence (AAAI), 2020.
(Oral)

Monte Carlo Tree Search in continuous spaces using Voronoi optimistic optimization with regret bounds

Beomjoon Kim, Kyungjae Lee, Sungbin Lim, Leslie P. Kaelbling, Tomás Lozano-Pérez.
AAAI Conference on Artificial Intelligence (AAAI), 2020.
(Oral)

Learning value functions with relational state representations for guiding task-and-motion planning

Beomjoon Kim, Luke Shimanuki.
Conference on Robot Learning (CoRL), 2019.

Adversarial actor-critic method for task and motion planning problems using planning experience

Beomjoon Kim, Leslie P. Kaelbling, Tomás Lozano-Pérez.
AAAI Conference on Artificial Intelligence (AAAI), 2019.
(Oral. 6% acceptance rate)

Regret bounds for meta Bayesian optimization with an unknown Gaussian process prior

Beomjoon Kim*, Zi Wang*, Leslie P. Kaelbling. (* indicates equal contribution)
Neural Information Processing Systems (NeurIPS), 2018.
(Spotlight. 3.5% acceptance rate)

Guiding search in continuous state-action spaces by learning an action sampler from off-target search experience

Beomjoon Kim, Leslie P. Kaelbling, Tomás Lozano-Pérez.
AAAI Conference on Artificial Intelligence (AAAI), 2018.
(Oral)

Learning to guide task and motion planning using score-space representation

Beomjoon Kim, Leslie P. Kaelbling, Tomás Lozano-Pérez.
IEEE International Conference on Robotics and Automation (ICRA), 2017.
(Winner of Best Cognitive Robotics Paper Award)

Generalizing over uncertain dynamics for online trajectory generation

Beomjoon Kim, Leslie P. Kaelbling, Tomás Lozano-Pérez.
International Symposium on Robotics Research (ISRR), 2015.

Learning from limited demonstrations

Beomjoon Kim, Amir M. Farahmand, Joelle Pineau, Doina Precup.
Neural Information Processing Systems (NeurIPS), 2013.
(Spotlight. 4% acceptance rate)

Maximum mean discrepancy imitation learning

Beomjoon Kim, Joelle Pineau.
Robotics: Science and Systems (RSS), 2013.

**Research
Experience**

Research Assistant, Reasoning and Learning Lab, McGill University.
Montreal, QC. Jan 2012 - Dec 2013

Developed novel reinforcement and imitation learning methods and applied them to the path planning for a robotic wheelchair. Advised by Joelle Pineau.

Research Assistant, Reasoning and Learning Lab, McGill University.
Montreal, QC. Jan 2011 - April 2011

Applied a POMDP solver to the user intention inference problem for a robotic wheelchair. Advised by Joelle Pineau.

Research Assistant, Department of National Defence - Center for operational R&D.
Ottawa, ON. Sept 2008 - Dec 2008

Developed a novel genetic algorithm for an aircraft cargo-loading problem. Advised by Bohdan L. Kaluzny.

**Teaching
Experience**

Teaching Assistant for 6.036 Intro to Machine Learning, MIT.
Boston, MA. Sept 2017 - Dec 2017

Helped design exams, weekly labs, and problem sets. Held office hours and answered questions on the course on-line forum to help students with course materials.

**Industry
Experience**

Machine Learning Engineer, Thalmic Labs.
Waterloo, ON. Jan 2014 - April 2014

Developed a gesture recognition algorithm for a gesture-controlled human-computer interaction device.

Digital Signal Processing Algorithm Developer, ON Semiconductor.
Waterloo, ON. Jan 2010 - April 2010

Developed noise reduction and echo cancellation algorithms for cell phone chips.

Software Consultant, Engenuity Corporation.
Toronto, ON. May 2009 - Aug 2009

Developed diverse software for different customer enterprises. Web development using JQuery and embedded system development for medical equipment.

Awards

ICRA Best Cognitive Robotics Paper Award, 2017
McGill GREAT Award, 2013
NSERC Undergraduate Student Research Award, 2010
University of Waterloo Full-time Bursary (merit-based), 2007-2011
University of Waterloo President's Scholarship, 2007