

Statement of Research Interests

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My research interests have primarily focused on leveraging a robots' past experiences to improve its motion planning performance in future similar problems. Specifically, I am interested in improving sampling-based planners. Specifically, I have focused on sampling-based conditional sampling-based planners. Ideally, a robot's past *experiences* should inform future actions in order to improve performance over time. by (1) learning to exploit similarities between motion planning problems and (2) creating adaptive algorithms that use prior experience and are robust across a wide range of scenarios.

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References

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