

Gholibjon Qasobov

Automation and Robotics Engineer

 qasobovgholib@gmail.com |  +7 (707) 350 61 34 |  Portfolio |  Gholibjon Qasobov |  golibqasobov

Skills and Interests

Programming Languages: C++, Python, MATLAB, IEC 61131-3 (ST, LD)

Robotics: ROS1 Noetic, ROS2 Humble, RoboDK, Nav2, Gazebo, Computer Vision, Machine Learning, Reinforcement Learning, Isaac Sim & Isaac Lab

Electronics and Hardware Skills: Raspberry Pi 4/5, ESP32, Nvidia Jetson, OpenCR, Modicon M340/M241 PLCs, Lidar (LS-LIDAR-C32, LDS-02), Intel RealSense D435i

Design & Prototyping: Autodesk Fusion 360, 3D Printing

Software & Tools: Git, GitHub, Linux, Docker, Jenkins

Experience

Robotics Laboratory Assistant, Kazakh-British Technical University January 2024 - Present

- Developed an automated inspection system using a mobile-legged robot with integrated elevator control, reaching 95 % inspection accuracy and 90 % success in multi-floor transitions.
- Collaborated on designing and simulating an innovative dual-function end-effector integrating a screwdriver and suction cup for automated power bank assembly using RoboDK
- Built an AprilTag-based pick-and-place system using a DoBot robotic arm, enabling 95 % positioning accuracy and autonomous object handling within a 30 cm workspace.
- Contributions to the development of laboratory practice manuals and documentation for robotics laboratory work.

Robotics Software Engineer, Alma Valley - Borealis Laboratory November 2024 – May 2025

- Recorded Raspberry Pi tutorials for Uni-X platform to support educational initiatives.
- Designed an autonomous water drone for environmental cleanup using NVIDIA Jetson Orin NX and RealSense D435i, achieving 90 % detection accuracy and 2 kg debris capacity.
- Developed a Kazakh voice control system for the Unitree Go2 robot using an offline LLM integrated with ROS2 Humble.

Research Intern, Constructor Knowledge Labs, Zurich, Switzerland (remote) June 2025 - August 2025

- Researched and implemented Retrieval-Augmented Generation (RAG) for multi-domain question answering.
- Focused on optimizing context retrieval and structured response generation using Large Language Models (LLMs).
- Evaluated system performance across diverse domain corpora to improve accuracy and coherence.

Projects

Autonomous Warehouse Mobile Robot Integration Using TurtleBot3 and OPC U

([Publication](#) ↗)

- Collaborated on developing a LIDAR-based navigation and grid-positioning algorithm for the TurtleBot3 Waffle Pi to enable autonomous warehouse operation. Integrated a 3D-printed lifting mechanism and OPC UA connectivity with Wires Board 7 and Honeywell Experion PKS for seamless industrial communication.
- Tools Used: Python, ROS1 Noetic, Wires Board, Honeywell Experion PSK, Fusion360

Autonomous Multi-Floor Inspection Mobile Legged-Robot with Elevator

Integration

- Designed and implemented an autonomous inspection mobile legged-robot capable of elevator-assisted

multi-floor navigation, achieving 95 % inspection precision and 90% reliability in floor transitions.

- Tools Used: C++, Python, ROS2 Humble, Nav2, Fusion-360, OpenCV, YOLO

Semi-Autonomous Water Drone for Trash Collection with Computer Vision

- Collaborated in developing of a semi-autonomous water drone for trash collection with 90% detection accuracy, 4h continuous operation, and 2 kg debris capacity
- Tools Used: Python, C++, YOLOv11, Nvidia Jetson Orin Nx, RealSense d435i camera, Fusion-360

Design and Simulation of a Dual-Function End-Effector for KUKA Power Bank Assembly

- Co-designed and simulated an innovative dual-function end-effector integrating a screwdriver and suction cup for automated power bank assembly
- Tools Used: RoboDK, KUKA, Fusion-360

Vision-Guided Pick-and-Place System Using AprilTag Recognition

- Designed and implemented a vision-based pick-and-place system using the DoBot Magician manipulator and AprilTag markers for precise object localization, achieving 95% placement accuracy within a 30 cm workspace
- Tools Used: Python, ROS1 Noetic, Fusion-360

Tic-Tac-Toe Playing Robot Against Human

- Designed and implemented an interactive Tic-Tac-Toe-playing robot using the DoBot Magician manipulator, YOLOv8 object detection, and the minimax algorithm.
- Tools Used: Python, ROS2 Humble, Fusion-360, YOLO

Activities and Achievements

Digital Bridge 2025 Robotics Hackathon Winner: Developed an autonomous navigation system for the Unitree Go2 robot dog to patrol complex maze-like environments, with a custom web interface for setting routes and viewing live camera feedback.

KazEnergy Eco-Shell Finalist: Recognized for the innovative design and implementation of a Semi-Autonomous Water Drone for trash collection.

Electrical Engineering Olympiad Finalist: Demonstrated excellence in problem-solving and electrical engineering concepts at olympiad held by Satpayev University.

Judge in Robo-Football competition: Served as a judge in Robo-Football competition in ITFest 2024.

Education

Kazakh-British Technical University, BS in Engineering and Technology

Sept 2022 – May 2026

- **Coursework:** Foundations of Electrical Engineering, Theory of Linear and Non-linear Control Systems, Autonomous Mobile Robots, Industrial Robot Operations, Introduction to Machine Learning, PLC Programming, Automation Components and Devices, Robotics in Manufacturing

Portfolio

Feel free to check my specific  [Portfolio ↗](#) entry for more details!