

Guillaume de Chambrier

Avenue de la Gare 3 – 1020 Renens – Switzerland • Born 29.06.1987

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🌐 <http://lasa.epfl.ch/people/member.php?SCIPER=213946.com> • Swiss and British

Profile

With several independent projects, I am an expert in developing and applying machine learning techniques to robot systems and I possess meticulous strong analytical skills.

Education

PhD in Manufacturing Systems & Robotics **École polytechnique fédérale de Lausanne, Switzerland**

- Thesis: Learning Search Strategies from Human Demonstrations 2012 - 31.08.2016
supervisor: Prof. Aude Billard

First class Master of Informatics with Honours Informatics **University of Edinburgh, UK**

- Thesis: Building and Controlling a Hexapod Robot 2006 - 2011
supervisor: Dr. Michael Herrmann

Erasmus Exchange, Bachelor **Universität des Saarlandes, Germany**
2008 - 2009

Experience

Teaching Assistant **École polytechnique fédérale de Lausanne**

- Course: Applied Machine Learning (MSc) 2013-2016
- Course: Advanced Machine Learning (MSc)

European Project **École polytechnique fédérale de Lausanne**

- Flexible Skill and Intuitive Robot Tasking 2012-2013

Supervision **École polytechnique fédérale de Lausanne**

- Akshara Rai (Msc student) 2013

Technical Skills

Programming: C/C++, Python, Java, MATLAB

Expertise: Robotics, Reinforcement Learning, Non-parametric Bayesian inference, Machine learning & Computer Vision

Languages

French, English (first language)

Awards and Certification

Google Prize: Best Phase 1 Project in Master of Informatics Programme (2010)

Publication

de Chambrier G., Billard A.: Learning search behaviour from humans. International Conference on Robotics and Biomimetics, Dec. 2013

Rai A., de Chambrier G., Billard A.: Learning from Failed Demonstrations in Unreliable Systems. International Conference on Humanoid Robots, Oct. 2014

de Chambrier G., Billard A.: Learning search policies from humans in a partially observable context. Journal of Robotics and Biomimetics, 2014

de Chambrier G., Billard A.: Fitted Policy Iteration for a POMDP Peg-In-Hole search task. Journal of Robotics and Autonomous Systems, 2016

de Chambrier G., Billard A.: Non-parametric Bayesian State Space Estimator for Negative Information. Frontiers in Robotics and AI, 2016 (*under review*)