

Mohak Bhardwaj

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📁 [mohakbhardwaj.github.io](https://github.com/mohakbhardwaj)

Education

- 2015–2016 **Carnegie Mellon University, Pittsburgh,**
Master of Science In Robotic Systems Development, *QPA:3.83/4.0.*
Relevant Coursework: Mobile Robots, Computer Vision, Robot Autonomy, Dynamic Optimization, Statistical Techniques in Robotics, Planning, Execution and Learning, Manipulation Algorithms
- 2011–2015 **Indian Institute of Technology(BHU), Varanasi, India,**
B.Tech in Mechanical Engineering.

Journal and Conference Publications

- Choudhury S., **Bhardwaj M.**, Arora S., Kapoor A., Ranade G., Scherer S., Dey D., "Data-driven Planning via Imitation Learning", International Journal of Robotics Research(IJRR), 2017(Submitted) **Pre-print:** goo.gl/6ABoZf
- Bhardwaj, M.**, Choudhury S., Scherer S., "Learning Heuristic Search via Imitation", Conference on Robotic Learning 2017 **Proceedings:** goo.gl/cPo2yQ
- Mithun, P., Anurag, V. V., **Bhardwaj, M.**, Shah, S. V., "Real-Time Dynamic Singularity Avoidance while Visual Servoing of a Dual-Arm Space Robot", Advances in Robotics 2015 **Proceedings:** goo.gl/j1uVLg

Work Experience

- Dec 2017- **Near Earth Autonomy, Robotics Engineer.**
Adaptive motion planning under uncertainty for real-world UAVs..
- Mar 2017-Dec 2017 **Air Lab, CMU, Extern,** Advisor: Dr. Sebastian Scherer.
Research on reinforcement and imitation learning applied to search based planning; Planning under uncertainty.
- Feb 2016-Dec 2016 **Air Lab, CMU, Research Associate,** Advisor: Dr. Sebastian Scherer.
Research on motion planning for UAV emergency landing.
- May 2016-Aug 2016 **Qualcomm R&D, Intern, Autonomous Driving,** Manager:Sebastian Mounier.
S.L.A.M and multi-sensor calibration for autonomous cars.
- May 2014-Aug 2014 **Robotics Research Institute, IIIT-Hyderabad, Intern,** Advisor: Dr. Suril V Shah.
Research on optimal control algorithms for space manipulators.

Research Work

- Dec 2016-July 2017 **Learning Heuristic Search via Imitation, Carnegie Mellon University.**
Proposed a formulation of graph search as sequential decision making and developed a novel algorithmic framework for learning heuristic policies using imitation learning. Trained neural network policies to explicitly minimize search effort by selecting next vertex to expand.
- Mar 2017- **Risk-Aware Stochastic Motion Planning for UAV Contingency Response, Carnegie Mellon University.**
Developing a robust motion planning architecture for UAVs that optimizes for closed loop performance under dynamics uncertainty to respond to a suite of emergency conditions (vehicle damage, loss of power etc.)

May 2014-Jul 2014 **Visual Servoing with Singularity Avoidance for Dual-Arm Space Robot**, *IIT-Hyderabad*.

Developed IK based optimal control algorithms for visual servoing of space manipulators with real-time singularity avoidance in a coupled arm-base dynamic system.

Project Work

Aug 2015-May 2016 **Motion Planning and Online Learning for Autonomous Driving**, *Master's Capstone Project*.

Developed real-time state lattice based motion planner for autonomous cars with differential constraints using ROS-C++.

Devised an online reinforcement learning method for dynamically allocating parking spots to autonomous cars using a multi-armed bandit formulation.

May 2016-Aug 2016 **Multi-sensor calibration using S.L.A.M for Autonomous Cars**, *Qualcomm R&D*.

Created a full-vehicle calibration room and developed software for multi-camera intrinsic calibration using factor graph SLAM and lidar to camera registration.

Sep 2016-Jan 2017 **End-to-End Reinforcement Learning with Deep Deterministic Policy Gradients**.

Applied off-policy learning for manipulation to grasp and pick up objects in simulation using OpenRAVE.

July 2016-Sep 2017 **Deep Reinforcement Learning using Actor-Critic Policy Gradient**, *Code:*

goo.gl/lzGQjW.

Experimented with deep RL algorithms for continuous control using an actor-critic setting with monte-carlo policy evaluation and Generalized Advantage Estimation. **Webpage:** goo.gl/CcdPo3

Aug 2014-May 2015 **Stable Walking of a Quadrupedal Robot**, *B.Tech Final Year Project*.

Led a four member team to design, simulate and implement statically stable crawl gait on a quadrupedal robot with 3DOF legs.

Open-Source Code

Search as Imitation Learning: Tensorflow pipeline for learning heuristic policies for search based motion planning. Link: goo.gl/YXkQAC

Python Motion Planning: Easy-to-use motion planning library geared towards planning and ML research Link: goo.gl/88shhJ

Deep RL with OpenAI Gym: Modular pipeline for developing and testing RL agents with OpenAI gym environments. Link: goo.gl/8tkFC4

Motion Planning Datasets: Benchmarks for comparing planning algorithms. Link: goo.gl/H6FqfV

Achievements and Honors

2011 Secured a rank in 0.6 % out of 480,000 students from all over India in the IIT Joint Entrance Examination

2015 Received Institute Color Award from IIT, Varanasi for outstanding extra-curricular achievements.

Technical Skills

Languages C++, Python

Software ROS, TensorFlow, OMPL

Hardware Nvidia Jetson, Beaglebone, Raspberry Pi