

# Kartik Paigwar

kartikp@iisc.ac.in | k.kartikpaigwar@gmail.com  
linkedin : [linkedin.com/in/kartikpaigwar](https://www.linkedin.com/in/kartikpaigwar)  
webpage : [kartikpaigwar.github.io](https://kartikpaigwar.github.io)  
+91-85-520-50534

---

## EDUCATION

- Arizona State University**, Tempe, USA *Jan' 21 - Jan' 23*  
*Master of Science*, Robotics and Autonomous Systems (Concentration in AI)
- Visvesvaraya National Institute of Technology**, Nagpur, India *Jul' 15 - Jun' 19*  
*Bachelor of Technology*, Computer Science and Engineering

---

## RESEARCH INTERESTS

Robot Learning, Human-Robot Interactions, Computer Vision, Control, Navigation

---

## PUBLICATIONS

- K. Paigwar**, L. Krishna, S. Tirumula et al. “Robust Quadrupedal Locomotion on Sloped Terrains: A Linear Policy Approach”. In *4th Conference on Robot Learning (CoRL)*, 2020. (Video)
- S. Tirumula, S. Gubbi, **K. Paigwar** et al. “Learning Stable Manoeuvres in Quadruped Robots from Expert Demonstrations”. In: *29th International Conference on Robot & Human Interactive Communication (Ro-Man)*, 2020. (Video)
- S. Tirumula, A. Sagi, **K. Paigwar** et al. “Gait Library Synthesis for Quadruped Robots via Augmented Random Search”. *arXiv preprint arXiv:1912.12907*, 2019. (Video)
- U. Patil et al. “Deep Learning Based Stair Detection and Statistical Image Filtering for Autonomous Stair Climbing”. In: *2019 Third IEEE International Conference on Robotic Computing (IRC)*.
- Y. Phalak, G. Charpe, **K. Paigwar**. “Omnidirectional Visual Navigation System for TurtleBot Using Paraboloid Catadioptric Cameras”. In: *2018 International Conference on Robotics and Smart Manufacturing (RoSMa)*. (Video)

---

## EXPERIENCE

**Indian Institute of Science, Bangalore, India** *Jun '19 - Present*  
*Project Associate, StochLab* *(Prof. Shishir K., Prof. Shalabh B.)*

### Learning Agile Locomotion for a Low Cost Quadruped Robot - Stoch2

- Designed a linear policy control framework for robust quadruped locomotion on sloped terrain using proprioceptive feedback.
- Generated stable foot trajectories for Omni-directional quadruped motion and learnt smooth transitions between these trajectories using expert demonstration.
- Worked on generating a library of walking gaits, namely trot, side-step, and turn by learning the optimal control points of cubic spline trajectories using Augmented Random Search.

### State Estimation and Localization for Autonomous Staircase Climbing

- Detected and performed 3D modeling of the staircase to estimate physical dimensions like height, width and inclination of the steps using onboard stereo camera on Stoch2.
- Installed electronic image stabilization and used MLS surface reconstruction method to smoothen the noisy point cloud data.

**Politecnico di Milano, Milan, Italy** *Jun '18 - Aug '18*  
*Undergraduate Summer Research Fellow, AIRLab* *(Prof. Andrea Bonarini)*

- Worked on an inverse reinforcement learning problem to find a reward function which could explain the strategies incorporated for robot teleoperation during search and rescue missions.
  - Created a tele-operated setup to perform expert's demonstration to search for an object in a partially observable environment.
  - Reduced the high dimensionality of robot's state space by encoding 2D Laser Scans (majorly accountable) using a 1D convolution autoencoders with a compression ratio of 7:1 and reconstruction accuracy of 93%.
- 

## RESEARCH PROJECTS

### Human Gameplay Imitation Through Deep-RL (B.Tech. Thesis)

Computer Science Department, VNIT, Nagpur, India | [Dataset](#), [Codes](#), [Video](#)

Aug '18 - Apr '19

(Prof. M. Dhabu)

- Designed a Deep RL framework for autonomous skills acquisition in which an agent learns from expert's gameplays to exhibit a repertoire of skills in an adaptive game environment.
- Demonstrated results over the Atari game, Breakout, where the agent mimics some of the intelligent skills in the game, namely, tunnelling, corner hitting and ball tracking to beat the average high score of human-players.

### Autonomous Multi-Storey Surveillance Robot (More Info)

IoLabs, VNIT, Nagpur | [Dataset](#), [Video](#)

Aug '18 - Jan '19

(Prof. Shital Chiddarwar)

- Designed and built a bio-inspired robot with continuous caterpillar tracks capable to traverse over the rough terrains including staircase of standard dimensions.
- Enabled multi-floor exploration via real time staircase detection and localization to autonomously climb over the staircase.
- Created an annotated staircase dataset with more than 2000 images to train a YOLO-v3 object detection model for robust detection over traditional methods of manually tuning the edge detector.
- Processed region of interest around the staircase using statistical gradient filters to find the heading offset of the robot with respect to stair's edges.

### Multi-Focus Image Fusion with Deep CNNs (More Info)

IoLabs, VNIT, Nagpur, India

Nov '17 - Mar '18

(Prof. Shital Chiddarwar)

- Aim of the project is to capture fully focused images with a minimal specification smartphone camera by fusing multiple images of the same scene taken with different focal settings of the camera.
  - Trained a Siamese CNN as a classifier using high definition images and their corresponding Gaussian blurred versions to obtain an all-in-focus image as described in the [paper](#) by Yu Liu.
- 

## COURSE PROJECTS

### Autonomous Ground Control Points Detection and Localization

Course: Computer Vision | [Github Link](#), [Report](#)

Feb '19 - Apr '19

(Prof. Praveen Kumar)

- For [Photogrammetry](#) operations like precision drone mapping, [GCP](#) markers are detected and marked in the 4k resolution drone images autonomously for true global accuracy.
  - Designed a pipeline consisting of image processing and deep learning techniques to segment L-shaped GCPs and mark their centre, which has the maximum convexity defect.
  - Estimated real-time 6-DOF pose of the drone with respect to GCP markers using SolvePnP method.
- 

## RELEVANT COURSEWORK

**Academic Courses:** Data Structures & Program Design, Design & Analysis of Algorithms, Linear Algebra, Neural Networks & Fuzzy Techniques, Artificial Intelligence, Image & Video Processing, Computer Vision, Machine Learning

**MOOCs:** Introduction to Machine Learning, Andrew Ng; Deep Learning Specialization, Andrew Ng— Coursera, Reinforcement Learning, David Silver; Introduction to Computer Vision— Udacity

---

## COMPUTER SKILLS

**Languages:** C, C++, Python, Java

**Research Tools and Libraries:** ROS, OpenCV, PCL, PyTorch, TensorFlow, Matlab, PyBullet

**Misc. Tools:** L<sup>A</sup>T<sub>E</sub>X, Android, Photoshop

---

## SERVICE

**Core-Coordinator, IvLabs**

May'18 - May'19

- Managed lab website, conducted weekly knowledge sharing sessions and key involvement to setup alumni funds.

**Project Mentor, IvLabs**

Jun'17 - Present

- Projects: [Wizards Chess](#), [Rapid Prototyping Educational Robotic Platform](#), [AutoExMap](#)

**Committee, ACM Programming Club, VNIT**

Jun'17 - Jun'18

- Conducted online coding competitions on Hackerearth and CodeChef for encouraging the programming culture in college.

---

## ACHIEVEMENTS

**Selected** for [Deep Learning Reinforcement Learning Summer School](#), 2020 hosted by CIFAR, Mila, Alberta Machine Intelligence Institute (Amii), and Vector Institute among more than 1000 applicants across the world.

**Recieved highest grades** for outstanding performance in Bachelor's thesis project, Computer Science Department, VNIT

**Qualified for Quarterfinals, DST & Texas Instrument India Innovation Challenge 2017**

---