Ph.D COURSE ROBOTICS AND INTELLIGENT MACHINES CURRICULUM INDUSTRY 4.0 (10797), XL CICLO

Following the assessment of qualifications (Step 1), the below candidates:

ID	Surname	Name	Research Theme 1	Research Theme 2	Research Theme 3	Total
8093635	AMINHATAMY	ERFAN	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	ROBUST AND EFFICIENT ROBOTIC PLATFORMS FOR VERSATILE APPLICATIONS		40
7731132	AZHAR	MUHAMMAD HAMZA	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	ROBUST AND EFFICIENT ROBOTIC PLATFORMS FOR VERSATILE APPLICATIONS	AI-AUGMENTED CONTROL FOR ROBOTS AND HUMANS TEAMING IN MANUFACTURING	41
4642233	BERRETTA	DARIA	COOPERATIVE MODELS AND CONTROL IN HUMAN-ROBOT COLLABORATION SCENARIOS			52
4662264	BORELLI	SIMONE	GENERATING WHOLE-BODY AVOIDANCE MOTION THROUGH LOCALIZED PROXIMITY SENSING FOR HUMAN-ROBOT COOPERATIVE OPERATIONS			55

8043465	DE BONIS	EMANUELE	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	SOFT ROBOTICS FOR ARCHEOLOGY		41
7981810	DEJENE	LIDIYA ABEBE	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	COOPERATIVE MODELS AND CONTROL IN HUMAN-ROBOT COLLABORATION SCENARIOS	KNOWLEDGE ENGINEERING FOR COLLABORATIVE ROBOTICS	40
8129662	DU	ZHEYU	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	COOPERATIVE MODELS AND CONTROL IN HUMAN-ROBOT COLLABORATION SCENARIOS		40
7926459	FODERARO	ELISA	KNOWLEDGE ENGINEERING FOR COLLABORATIVE ROBOTICS	GENERATING WHOLE-BODY AVOIDANCE MOTION THROUGH LOCALIZED PROXIMITY SENSING FOR HUMAN-ROBOT COOPERATIVE OPERATIONS	AI-AUGMENTED CONTROL FOR ROBOTS AND HUMANS TEAMING IN MANUFACTURING	55
8037954	GUARAGNELLA	GIOVANNA	AI-AUGMENTED CONTROL FOR ROBOTS AND HUMANS TEAMING IN MANUFACTURING			52
7698198	KASHMAR	OMAR	AUTONOMOUS INTERACTION CONTROL FOR HIGH FIDELITY SURFACE TREATMENT TASKS	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	GENERATING WHOLE-BODY AVOIDANCE MOTION THROUGH LOCALIZED PROXIMITY SENSING FOR HUMAN-ROBOT COOPERATIVE OPERATIONS	51
7921311	LI	CHANGHAO	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN	SOFT ROBOTICS FOR ARCHEOLOGY	AUTONOMOUS INTERACTION CONTROL FOR HIGH FIDELITY SURFACE TREATMENT TASKS	40

			UNPREDICTABLE ENVIRONMENTS			
7970700	LIU	QING	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	COOPERATIVE MODELS AND CONTROL IN HUMAN-ROBOT COLLABORATION SCENARIOS		51
8055389	LOVATO	ALESSIO	AUTONOMOUS INTERACTION CONTROL FOR HIGH FIDELITY SURFACE TREATMENT TASKS			50
7925623	PARK	DO WON	SOFT ROBOTICS FOR ARCHEOLOGY			51
5168055	RAVIKUMAR	NIRMAL KUMAR	SOFT ROBOTICS FOR ARCHEOLOGY			42
6580146	REHMAN	ATIF	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS	AUTONOMOUS INTERACTION CONTROL FOR HIGH FIDELITY SURFACE TREATMENT TASKS	AI-AUGMENTED CONTROL FOR ROBOTS AND HUMANS TEAMING IN MANUFACTURING	40
8000334	RODRIGUES	VINAYVIVIAN PEDRICK	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS			42
8134402	SHAIKH	HAMZA AHMED	ROBUST AND EFFICIENT ROBOTIC PLATFORMS FOR VERSATILE APPLICATIONS	SOFT ROBOTICS FOR ARCHEOLOGY		40
7756135	SONG	MIANZHI	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF			48

			ROBOTS IN UNPREDICTABLE ENVIRONMENTS			
5759635	UR-REHMAN	AQEEL-	ROBUST AND EFFICIENT ROBOTIC PLATFORMS FOR VERSATILE APPLICATIONS			40
8127725	WANG	JIAMING	REINFORCEMENT LEARNING AND FOUNDATIONAL MODELS FOR ADAPTIVE CONTROL OF ROBOTS IN UNPREDICTABLE ENVIRONMENTS			49

are invited to the online interview (Step 2 - oral examination) on Thursday 23th January at 9.00 (Central European Time) through the Teams call:

https://u.garr.it/Gsufc

If you have problems connecting, please feel free to contact Prof. Simetti by email at enrico.simetti@unige.it

Candidates will be required to exhibit a valid identification document prior to starting the interview and they will need to fill in and sign a Self-Declaration Affidavit (according to art. 47 and art.19 of D.P.R. n. 445/2000) after the interview. The blank form will be distributed during the interview session.