

ANMOL GUPTA

anmolgupta@asu.edu [◇ Google Scholar](#) [◇ LinkedIn](#) [◇ GitHub](#) [◇ Portfolio](#)

EDUCATION

Arizona State University, Tempe, AZ

August 2024 - Present

PhD in Computer Engineering (Computer Systems), GPA - 3.97/4.00

Arizona State University, Tempe, AZ

August 2022 - May 2024

M.S. in Computer Engineering (Computer Systems), GPA - 3.83/4.00

Maulana Azad National Institute of Technology, India

August 2017 - April 2021

B. Tech. in Electronics and Communication Engineering, GPA - 7.98/10.00

PUBLICATIONS

Monkey See, Can Monkey Do? A Benchmark for Evaluating Robot Skill Learning by Observation

Weiwei Gu*, Anmol Gupta*, Anant Sah*, Ryan Sam Varghese, Lalitha Vanam, Prabhath Adireddi, Peter Karkus, Nakul Gopalan

Conference on Robot Learning (CoRL), 2026 [↗](#)

PokeNet: Learning Kinematic Models of Articulated Objects from Human Observations

Anmol Gupta, Weiwei Gu, Omkar Patil, Jun Ki Lee, Nakul Gopalan

IEEE International Conference on Robotics and Automation (ICRA), 2026 [↗](#)

Continual Robot Skill and Task Learning via Dialogue

Weiwei Gu, N. Suresh K. Kondepudi, Anmol Gupta, Lixiao Huang, Nakul Gopalan

Under Review [↗](#)

RESEARCH EXPERIENCE

RoboReel: Benchmarking Robot Skill Learning from Human Videos

CoRL 2026

- Designed RoboReel, a learning-from-observation benchmark that pairs real-world human demonstration videos with calibrated ManiSkill/SAPIEN digital-twin environments across 10 manipulation tasks.
- Evaluated over seven learning-from-observation methods, including video-conditioned $\pi_{0.5}$ variants, to characterize robustness to distractors, task horizon, and manipulation precision.

PokeNet: Articulation Modeling from Human Video Demonstrations

ICRA 2026

- Developed an end-to-end framework that estimates articulated-object joint parameters, manipulation order, and joint states from a single human demonstration without prior object knowledge.
- Improved joint-axis and joint-state estimation accuracy by over 27% on diverse and unseen object categories, with evaluation in simulation and the real world.

Real-to-Sim-to-Real VLA Deployment

Robot Learning

- Recreated real manipulation scenes in ManiSkill using SAM3D-objects and Blender to support sim-to-real VLA training and evaluation.
- Used VLM-derived task decomposition, GraspGen candidate grasps, and MPlib motion planning to generate robot demonstrations from language commands.
- Demonstrated real-world VLA deployment with an absolute 19% success-rate improvement.

Continual Robot Skill and Task Learning via Dialogue

Under Review

- Designed a continual robot-learning framework that uses grounded dialogue to query and acquire novel skills from human users.
- Developed and evaluated ACT-LoRA, a parameter-efficient visuomotor policy for learning new skills from few demonstrations; the approach achieved over 300% improvement on novel skills while retaining performance on existing skills.

PROFESSIONAL EXPERIENCE

e2Serv Technologies: Software Development Engineer

August 2021 - June 2022

- Built backend services for an employee-management system using Java, Spring Framework, Thymeleaf, and JPA.

Swaayatt Robots: Deep Learning Intern

January 2021 - July 2021

- Developed a Fast R-CNN traffic-sign recognition system with style-transfer and conditional-GAN data augmentation, achieving 87% accuracy on a challenging Indian road-scene dataset.