



Giulio Campagna

📍 **Work** : Fibigerstræde 16, 9220, Aalborg, Denmark

✉ **Email**: giulio.campagna3@gmail.com ✉ **Email**: gica@mp.aau.dk

☎ **Phone**: (+39) 3757770124 📠 **Phone**: (+45) 22543373

🌐 **Website**: <https://www.campagna-robotics.com/>

🌐 **Website**: <https://vbn.aau.dk/en/persons/153215>

🌐 **Website**: <https://scholar.google.com/citations?user=2YTOXC4AAAAJ&hl=en&oi=ao>

🌐 **LinkedIn**: <https://www.linkedin.com/in/giulio-campagna-7505881a4>

Gender: Male **Date of birth**: 03/05/1995 **Place of birth**: Siena, Italy **Nationality**: Italian

ABOUT ME

Eng. Giulio Campagna, PhD

IEEE Member

IEEE Robotics and Automation Society Member

2018: Received a **B.Sc. degree in Computer and Information Engineering** from the University of Siena (Italy), with a thesis entitled "*Experimentation on Real Video Systems for Object Detection.*" The Bachelor's program covered a wide range of courses in Computer Science, Automation, Telecommunications, and Electronics.

2021: Received an **M.Sc. degree in Computer and Automation Engineering**, specializing in Robotics and Automation, from the University of Siena (Italy). The Master's thesis was entitled "*Commanding Grasping Robot through Virtual Reality and Simulated Wrenches.*" This program provided advanced knowledge in artificial intelligence, machine learning, industrial automation, and robotics. Additionally, completed **Erasmus studies** at the Technical University of Munich and an **Erasmus traineeship** at Aarhus University.

2022: Qualified as a **Robotics and Automation Engineer** in Section A, Information Engineering Sector, Class LM-32, from the University of Florence (Italy).

2022: The Master's thesis was registered in the Italian database **PubbliTesi** in recognition of its outstanding quality.

2024: Finalist, Digital Sustainability Award – Recognized by the first Italian research foundation dedicated to digital sustainability.

2022–2025: PhD Fellow in Human-Robot Collaboration at **Aalborg University** (Denmark), Human-Robot Interaction Laboratory.

Research focused on developing machine learning algorithms leveraging multi-modal sensor data to enhance safety, foster trust, and promote ergonomic behavior. The aim was to create more user-friendly robot control systems for human operators in industrial human-robot collaboration. The PhD thesis, entitled "*Data-Driven Trust Assessment in Human-Robot Collaboration for Industrial Applications,*" was conducted under the **RETRO Project: Regulating Trust in Human-Robot Interaction**, funded by the Independent Research Fund Denmark (DFF Research Project 2, Grant No. 1032-00311B).

Furthermore, served as a **Visiting Researcher** at the **DLR - German Aerospace Center** and the **Italian Institute of Technology** (under the supervision of Dr. Arash Ajoudani).

Publications: Authored 11 peer-reviewed articles, including IEEE RO-MAN, IEEE ICRA, IEEE RA-L (IF: 5.3), and ACM THRI (IF: 5.5).

According to the [Best Global Universities rankings](#), Aalborg University is ranked **third** in **Europe** for **engineering**, following ETH Zurich and Imperial College London.

RESEARCH INTEREST

Research in **Human-Robot Collaboration** on **multimodal models** and **robot learning** for adaptive interaction, with a focus on trust, safety, and ergonomics in **Industry 5.0**. Expertise in **physical HRI**, **collaborative robotics**, and **machine learning** for user-centered systems. **Emerging interests** include **transfer learning**, **kinesthetic teaching**, and **foundational models**.

Google Scholar Metrics (as of November 2025): h-index: 5, i10-index: 3.

EDUCATION AND TRAINING

[15/01/2022 – 14/01/2025]

PhD in Human-Robot Collaboration

Aalborg University - Technical Faculty of IT and Design <https://vbn.aau.dk/en/persons/153215>

Address: Rendsburggade 14, 9000, Aalborg, Denmark | | **Level in EQF:** EQF level 8

The research aimed to develop **machine learning algorithms** that leverage **multi-modal sensor data** to enhance **safety**, **foster trust** and **ergonomic behavior**, and create more **user-friendly robot control systems** for human operators in **industrial human-robot collaboration**.

- Conduct independent research under the supervision of senior faculty members.
- Collaborate with fellow researchers and contribute to the development of research projects.
- Write and publish scientific articles in peer-reviewed journals.
- Participate in academic activities such as seminars, workshops, and conferences.
- Contribute to project deliverables and progress reports.
- Visiting researcher at the *German Aerospace Center (DLR)* and *Italian Institute of Technology* (under supervision of Dr. Arash Ajoudani)

Thesis: *Data-Driven Trust Assessment in Human-Robot Collaboration for Industrial Applications*

The PhD thesis was conducted under the *RETRO Project: Regulating Trust in Human-Robot Interaction*, funded by the Independent Research Fund Denmark (DFF Research Project 2, Grant No. 1032-00311B).

Publications: Authored 11 peer-reviewed articles, including IEEE RO-MAN, IEEE ICRA, IEEE RA-L (IF: 5.3), and ACM THRI (IF: 5.5).

Research Line: Human - Robot Collaboration

Laboratory: Human - Robot Interaction

[01/05/2024 – 30/06/2024]

Visiting Researcher

DLR - German Aerospace Center <https://www.dlr.de/en/zlp/about-us>

City: Augsburg | **Country:** Germany |

Conducted research on **user-friendly interfaces** for **human-robot collaboration** in **Industry 5.0** manufacturing systems. Developed and tested a control framework using natural modalities—**hand gestures and voice commands**—to **guide robot** movements during maintenance tasks. The scenario involved an industrial robot transporting carbon fiber fabric to a mold, where a human operator draped the material. While both steps are automated, micromanagement tasks like maintenance checks required manual control via a smartPAD, disrupting workflow. The proposed framework enabled seamless robot control through gestures and voice, reducing interruptions and supporting operators with limited robotics experience.

Experiments were conducted at the Center for Lightweight-Production-Technology, **German Aerospace Center** (DLR).

Publication: [Fostering Trust through Gesture and Voice-Controlled Robot Trajectories in Industrial Human-Robot Collaboration](#), *IEEE ICRA 2025*

[01/10/2023 – 29/02/2024]

Visiting Researcher

Italian Institute of Technology (IIT) <https://www.iit.it/>

City: Genoa | **Country:** Italy |

The novel framework leverages **Preference-Based Optimization** (PBO) and considers three renowned **interaction parameters**: the robot's velocity profile, the separation distance between the human and the robot, and the vertical proximity to the user's head. By continuously **refining** these parameters based on **qualitative feedback** from **human collaborators**, the system **adjusts** the **robot's trajectories** dynamically. This **feedback** was used as **ground truth** to train **machine learning models** capable of **predicting trust levels** from **human- and robot-related behavioral indicators**. The overall goal of this personalization is to promote a safe, ergonomic, and trustworthy human-robot interaction environment. A **chemical handling scenario** was developed as a testbed for evaluating the framework.

The experiments were conducted under the supervision of *Dr. Arash Ajoudani* at the Human-Robot Interfaces and Interaction Laboratory, **Italian Institute of Technology (IIT)**.

Publications:

- 1) [Promoting trust in industrial human-robot collaboration through preference-based optimization](#), *IEEE RA-L (IF:5.3)*
- 2) [Estimating Trust in Human-Robot Collaboration Through Behavioral Indicators and Explainability](#), *IEEE RA-L (IF:5.3)*

[30/09/2018 – 25/04/2021]

Master's Degree: Computer and Automation Engineering- Robotics and Automation

University of Siena - Department of Information Engineering and Mathematical Sciences <https://computer-automation.unisi.it/it>

Address: 56, Via Roma, San Niccolò, 53010, Siena, Italy | | **Level in EQF:** EQF level 7 |

Thesis: Commanding Grasping Robot through Virtual Reality and Simulated Wrenches

Link: <https://www.campagna-robotics.com/projects>

The program aims to provide advanced knowledge on the main technologies and applications of **artificial intelligence, machine learning, industrial automation, and robotics**. It equips participants with the skills necessary for the design, management, development, and technological innovation in the field of advanced hardware and software system architectures, as well as in control systems and robotics.

Thesis available [here](#)

Final Grade: Graduated with a final degree score of 109/110. The average grade across all exams fell short of the threshold required for the maximum score by only 0.06 points.

Projects:

- **Control of Allegro Hand Using ROS:** Developed a system for controlling the Allegro Hand through the Robot Operating System (ROS).

- *Machine Learning Algorithm for Atari Breakout*: Created a Python-based implementation of the classic game Atari Breakout, utilizing machine learning techniques to predict optimal moves for successful gameplay.
- *Project Decision Analysis: Cooperative Robots*: Designed a cooperative system where two robots transport an object from an initial to a final position while avoiding collisions. The project aimed to identify optimal policies that minimize costs, employing Dynamic Programming, Markov Processes, and Monte Carlo simulations.
- *Project Filtering Techniques: Network Agents*: Established a network of agents arranged in a ring structure to facilitate information exchange regarding their states. The objective was to estimate these states using both the Kalman Filter and Extended Kalman Filter.
- *Project Network Optimization: Lin-Kernighan Algorithm*: Implemented the Lin-Kernighan algorithm for network optimization purposes.

[31/08/2020 – 14/11/2020]

Erasmus Traineeship

Aarhus University (AU)

Country: Denmark |

Link: <https://www.campagna-robotics.com/commanding-grasping-robot>

Using Unity3D, a **virtual environment** was created to display an **avatar** of the **subject's hand**. Through the Oculus Rift, the user could see the **virtual hand**, **objects**, and a **contact-detection sphere** that **contained** the **target object** for **grasping**. The **hand's** position and rotation were **tracked** using **Optitrack Motive**, a precise tracking software for objects and rigid bodies. Forces applied by the hand to the sphere were transmitted through haptic devices, providing feedback on the generalized forces exerted.

[01/10/2019 – 31/03/2020]

Erasmus for Studies

Technical University of Munich (TUM)

City: Munich | **Country:** Germany |

Link: <https://www.campagna-robotics.com/projects>

Courses

- Dynamic Human-Robot Interaction (*Prof. Dongheui Lee*)
- Human-Centered Neuroengineering for Cybathlon (*Prof. Gordon Cheng*)
- Advanced Robot Control and Learning (*Prof. Sami Haddadin*)

Relevant Projects

- Developed a grasping algorithm designed for individuals with disabilities, enabling them to select objects by focusing on them with an eye-tracking device and indicating their intention to grasp using an EMG Myo armband. The various components are interconnected through the ROS framework.
- Participated in the *Robothon Competition*, focused on identifying types of waste and appropriately sorting them using the Franka Panda robot

[2014 – 2018]

Bachelor's Degree: Computer and Information Engineering

University of Siena - Department of Information Engineering and Mathematical Sciences <https://ing-informatica-informazione.unisi.it/it>

Address: 56, Via Roma, San Niccolò, 53010, Siena, Italy | **Level in EQF:** EQF level 6 |

Thesis: Experimentation for real video of systems for Object Detection

The program of study includes an in-depth exploration of foundational and specialized subjects in Information Engineering, offering a broad range of specialized courses in the fields of **Computer Science**, **Automation**, **Telecommunications**, and **Electronics**.

High School Graduation

Tito Sarrocchi Scientific and Technological High School

Address: 53010, Siena, Italy | **Final grade:** 100/100 | **Level in EQF:** EQF level 5

WORK EXPERIENCE

Aalborg University - Faculty of Engineering and Science - Department of Materials and Production <https://www.mp.aau.dk/research/research-areas/robotics-and-automation>

City: Aalborg | **Country:** Denmark

[15/03/2025 – 31/08/2025]

Research Assistant

Research focused on improving shop floor integration of **collaborative robots** by addressing **usability** and **training challenges** within the **Industry 5.0 framework**.

- Conducted literature review and technical analysis on collaborative robots in industrial environments.
- Supported data collection and user studies to assess worker training needs and cobot usability.
- Contributed to developing intuitive programming strategies aimed at improving shop floor adoption of cobots.
- **Publication:** Article currently under review at IEEE T-ASE (IF: 6.4)

Research Line: [Human - Robot Collaboration](#)

Research Group: [Robotics and Automation](#)

Laboratory: Smart Production

Aalborg University - Technical Faculty of IT and Design

City: Aalborg | **Country:** Denmark

Link <https://vbn.aau.dk/en/persons/153215>

[15/01/2022 – 14/01/2025]

PhD in Human-Robot Collaboration

The research aimed to develop **machine learning algorithms** that leverage **multi-modal sensor data** to enhance **safety**, **foster trust** and **ergonomic behavior**, and create more **user-friendly robot control systems** for human operators in **industrial human-robot collaboration**.

Research Line: Human - Robot Collaboration

Laboratory: Human - Robot Interaction

University of Siena

City: Siena | **Country:** Italy

Link <https://www.campagna-robotics.com/commanding-grasping-robot>

[02/12/2020 – 31/03/2021]

Master's Thesis Internship

This study aimed to **manipulate real-world objects through virtual reality**. Specifically, a **virtual hand** was **controlled** within the environment using a **CyberGlove III**, **IMU MPU 6050**, and **Leap Motion Controller**, facilitating real-time interaction. **Haptic feedback** was provided **during interactions** with virtual objects. The **motions** performed in the **virtual environment** were **replicated** in the **real world** by **teleoperating a robotic manipulator**, utilizing the object's pose in the virtual space.

Experiments were conducted at the *SIRSLab laboratory* at the University of Siena under the supervision of *Professor Domenico Prattichizzo*.

University of Siena

Address: 53010, Siena, Italy

This experiment involved analyzing **real-world videos** for **object detection** on **highways**. The primary objective was to identify and **classify various vehicles**, such as cars, using the OpenCV library, which is well-suited for image manipulation, tracking, and object recognition. The study aimed to enhance the accuracy and efficiency of vehicle detection in dynamic traffic environments.

RESEARCH SOCIAL PROFILES

Social Profiles for Research

- **ORCID:** 0000-0002-2422-1663
- **RESEARCHID:** ADG-0240-2022

- **SOCIAL PROFILES:**
 1. [Personal Website](#)
 2. [Aalborg University Profile](#)
 3. [LinkedIn](#)
 4. [ORCID](#)
 5. [Google Scholar](#)
 6. [ResearchGate](#)
 7. [Loop](#)
 8. [Web of Science](#)
 9. [Academia](#)
 10. [IEEE Collabratec](#)

PROJECT PROPOSALS & RESEARCH GRANTS

[2022 – 2025] **Project RETRO: Regulating Trust in Human-Robot Interaction**

Funded by the *Independent Research Fund Denmark* (DFF Research Project 2, Grant No. 1032-00311B).

(Budget: DKK 6 million; *Principal Investigator*: Prof. Matthias Rehm).

Contributed to project deliverables and progress reports.

Link: <https://vbn.aau.dk/da/projects/regulating-trust-in-human-robot-interaction/>

[2026 – 2028] **DFF Postdoctoral International Grant 2025**

Application submitted.

Funded by the *Independent Research Fund Denmark*.

(Budget: DKK 1.5 million; *Principal Investigator*: Dr. Giulio Campagna).

PUBLICATIONS

- [2025] [**Estimating Trust in Human-Robot Collaboration Through Behavioral Indicators and Explainability**](#)

Campagna, G., Lagomarsino, M., Lorenzini, M., Chrysostomou, D., Rehm, M., & Ajoudani, A. (2025). Estimating Trust in Human-Robot Collaboration Through Behavioral Indicators and Explainability. *IEEE Robotics and Automation Letters*.

[2024] [**Promoting Trust in Industrial Human-Robot Collaboration through Preference-Based Optimization**](#)

Campagna, G., Lagomarsino, M., Lorenzini, M., Chrysostomou, D., Rehm, M., & Ajoudani, A. (2024). Promoting Trust in Industrial Human-Robot Collaboration through Preference-Based Optimization. *IEEE Robotics and Automation Letters*.

[2025] [**Fostering Trust through Gesture and Voice-Controlled Robot Trajectories in Industrial Human-Robot Collaboration**](#)

Campagna, G., Frommel, C., Haase, T., Gottardi, A., Villagrossi, E., Chrysostomou, D., & Rehm, M. (2025). Fostering Trust through Gesture and Voice-Controlled Robot Trajectories in Industrial Human-Robot Collaboration. In *2025 IEEE International Conference on Robotics and Automation (ICRA)*. IEEE (Institute of Electrical and Electronics Engineers).

[2024] [**A Data-Driven Approach Utilizing Body Motion Data for Trust Evaluation in Industrial Human-Robot Collaboration**](#)

Campagna, G., Dadgostar, M., Chrysostomou, D., & Rehm, M. (2024). A Data-Driven Approach Utilizing Body Motion Data for Trust Evaluation in Industrial Human-Robot Collaboration. In *33rd IEEE International Conference on Robot and Human Interactive Communication, IEEE RO-MAN 2024*. IEEE.

[2024] [**Analysis of Facial Features for Trust Evaluation in Industrial Human-Robot Collaboration**](#)

Campagna, G., Chrysostomou, D., & Rehm, M. (2024, May). Analysis of Facial Features for Trust Evaluation in Industrial Human-Robot Collaboration. In *2024 IEEE International Conference on Advanced Robotics and Its Social Impacts (ARSO)* (pp. 1-6). IEEE.

[2024] [**Investigating Electrodermal Activity for Trust Assessment in Industrial Human-Robot Collaboration**](#)

Campagna, G., Chrysostomou, D., & Rehm, M. (2024). Investigating Electrodermal Activity for Trust Assessment in Industrial Human-Robot Collaboration. In *21st International Conference on Ubiquitous Robots (UR 2024)*. IEEE.

[2023] [**Analysis of Proximity and Risk for Trust Evaluation in Human-Robot Collaboration**](#)

Campagna, G., & Rehm, M. (2023, August). Analysis of proximity and risk for trust evaluation in human-robot collaboration. In *2023 32nd IEEE International Conference on Robot and Human Interactive Communication (RO-MAN)* (pp. 2191-2196). IEEE.

[2023] [**Trust Assessment with EEG Signals in Social Human-Robot Interaction**](#)

Campagna, G., & Rehm, M. (2023, December). Trust Assessment with EEG Signals in Social Human-Robot Interaction. In *International Conference on Social Robotics* (pp. 33-42). Singapore: Springer Nature Singapore.

[2025] [**An EEG Benchmark Data Set for Data-Driven Trust Assessment in Social HRI**](#)

Rehm, M., Pontikis, I., & Campagna, G. (2025). An EEG Benchmark Data Set for Data-Driven Trust Assessment in Social HRI. In *Proceedings International Conference on Social Robotics*. Springer.

[2024] [Does Robot Anthropomorphism Improve Performance and User Experience in Teleoperation?](#)

Villani, A., Baldi, T. L., D'Aurizio, N., Campagna, G., & Prattichizzo, D. (2024). Does Robot Anthropomorphism Improve Performance and User Experience in Teleoperation?. In *2024 IEEE-RAS International Conference on Humanoid Robots*.

[2025] [A Systematic Review of Trust Assessments in Human-Robot Interaction](#)

Campagna, G., & Rehm, M. (2025). A Systematic Review of Trust Assessments in Human-Robot Interaction. *ACM Transactions on Human-Robot Interaction (THRI)*.

[2019] [Commanding Grasping Robot through Virtual Reality and Simulated Wrenches](#)

Campagna, G. (2019). Commanding Grasping Robot through Virtual Reality and Simulated Wrenches.

PEER REVIEWER

Outlets

- **IEEE Robotics and Automation Letters (RA-L)**, 2 papers
- **IEEE International Conference on Robotics and Automation (ICRA)**, 1 paper

ACTIVITY

Trust, Acceptance and Social Cues in Human-Robot Interaction – SCRITA

Workshop at 32nd IEEE International Conference on Robot and Human Interactive Communication (RO-MAN 2023)

ASIMOV: Adaptive Social Interaction based on user's Mental mOdelS and behaVior in HRI

Workshop at 15th International Conference on Social Robotics (ICSR 2023)

[01/03/2022] **10th Annual Aalborg Robotics Workshop**

INTERNATIONAL RELATIONS

Collaborations

- **Academic:** Aalborg University, University of Southern Denmark, Aarhus University, TU Wien, University of Siena
- **R&D:** Italian Institute of Technology, German Aerospace Center, National Research Council of Italy – STIIMA
- **Industry:** IT+Robotics s.r.l

NETWORKS AND MEMBERSHIPS

[23/02/2022 – Current] **IEEE MEMBERSHIP**

Link: <https://www.ieee.org/>

[23/02/2022 – Current] **IEEE ROBOTICS & AUTOMATION SOCIETY (RAS) MEMBERSHIP**

Link: <https://www.ieee-ras.org/>

Link: <https://www.ieee-ras.org/human-robot-interaction-coordination>

[Current] **IDA (Ingeniørforeningen i Danmark)** Denmark

The Danish Society of Engineers, IDA is a professional body and trade union for technical and scientific professionals.

Link: <https://ida.dk/>

HONOURS AND AWARDS

[02/2022] **Qualification to the profession of Robotics and Automation Engineer in section A, Information Engineering sector, class LM-32**

Awarding institution: University of Florence

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_df1fe34317d74161a1e58cb14c91d199.pdf

[30/06/2022] **Registration of Master Thesis in Italian Database PubbliTesi for recognition of one among best thesis**

Awarding institution: PubbliTesi

Link: <https://www.linkedin.com/feed/update/urn:li:activity:6948250431697395712/>

[2024] **Finalist for the Digital Sustainability Award** **Awarding institution:** Fondazione per la Sostenibilità Digitale

Finalist for the Master's thesis for the first recognized research foundation in Italy dedicated to exploring topics related to digital sustainability

LANGUAGE SKILLS

Mother tongue(s): Italian

Other language(s):

English

LISTENING B2 READING C1 WRITING B2

SPOKEN PRODUCTION B2 SPOKEN INTERACTION B2

French

LISTENING A1 READING A1 WRITING A1

SPOKEN PRODUCTION A1 SPOKEN INTERACTION A1

Levels: A1 and A2: Basic user; B1 and B2: Independent user; C1 and C2: Proficient user

SKILLS

Tools & Technologies

EMG Myo Armband | Linux and Windows operative systems | Xsens | MATLAB | Git Hub | Latex | C and C++ | OpenCV | Franka Emika Panda Robot | Python | ROS | Universal cobots | Leap Motion | KUKA Robots | Industrial cameras | Optitrack Motive

Generic Skills

Digital Mindset | Digital Awareness | Knowledge Networking | Virtual Communication | Digital Team Working

Other skills and Applications

Machine Learning | Deep Learning | Reinforcement Learning | Dynamic Programming | Automation | Optimization | Object Detection | Teleoperation | Physical Human-Robot Interaction | Motion Tracking Systems | Multimodal Sensor Fusion | Industry 5.0 | Human-Robot Collaboration | Robotics | Collaborative Robots | Robot Learning

ORGANISATIONAL SKILLS

Organisational skills

- Team management
- Goal setting
- Decision-making skills
- Problem solving skills
- Strategic thinking and planning

COMMUNICATION AND INTERPERSONAL SKILLS

Communication and interpersonal skills

- Active listening
- Conflict resolution
- Good communication skills
- Emotional intelligence

DRIVING LICENCE

Cars: B

CERTIFICATIONS

FIRST

FIRST - University of Cambridge, 10 08 2021, Certificate Number: B6014466 - European Level: B2

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_b7ef89cc2c9d4016ac1b52f5f42035f0.pdf

PET

PET - University of Cambridge, 01 05 2014, Certificate Number: 0044043424 - European Level: B1

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_db96ce0b8949475280806ce046801885.pdf

DELF A1

DELF - DELF, 26 11 2009 - European Level: A1

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_b0c55e801df345f7903d46b02269a3b4.pdf

ECDL ADVANCED AM4

ECDL ADVANCED MODULE AM4, AICA, 19-01-2012, N° ADV026100

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_32ffe3230edc479fa3a2003bf9e572c9.pdf

ECDL CORE

ECDL CORE, AICA, 23-04-2010, N° IT 1526910

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_9975058b339a467c89d1134e5c705c34.pdf

"Formazione Generale Lavoratori" refers to general training for workers on workplace safety and regulations in Italy.

Corso AiFOS EL/350792, Attestato n. U185600

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_8c29b64fcf48442298b1b968f430e50c.pdf

COURSE

Deep Learning

- Machine learning fundamentals
- Deep learning concepts
- Deep learning methods including deep neural networks, long short-term memory recurrent neural networks, convolutional neural networks

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_8c2fd8c40d054f129506c4c059e295fa.pdf

Reinforcement Learning and Dynamic Programming

- Markov decision processes
- Dynamic programming for infinite time and stopping time
- Reinforcement learning

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_8d74c6afd42f4f36a580d71cb488ac93.pdf

Architecture of Machine Learning Systems

- Essential concepts of modern Machine Learning systems
- TensorFlow
- Machine Learning pipelines.

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_a2999cf1b607485baf3c06d5a6131e46.pdf

Data Quality Management

- Provide an overview of the most effective assessment and improvement techniques
- Discuss the main data quality issues in data integration
- Data Profiling
- Data Cleaning

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_d3728e11d03242d9927f57d67cf74182.pdf

Data and Machine Learning Operations

- Data Augmentation
- Labeling
- Cleaning
- Pre-processing
- Transfer learning

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_77f754ae9f3049dfb5350b148f939d96.pdf

Signal and Spectral Analysis extracting information from noisy data

- Filtering, statistical signal processing, estimation theory, maximum likelihood, power spectral density estimation, modelling, least squares, autoregressive, nonnegative matrix factorizations, sparsity, periodic signals, Fourier analysis, line spectra.

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_4cdfa6600eb54a7d992200e7a6b3be32.pdf

Management of Research and Development

- Insight in how to carry out R&D projects in an organizational context and how to manage own projects.

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_733b2466c966484b9b6895c540e0fb4d.pdf

Academic Writing in English

- English academic writing

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_74296c5533e249da9ac168e3b9df274c.pdf

Writing and Reviewing Scientific Papers

- Writing and reviewing scientific papers

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_0ad760830eee4d728c7d721bb1f2f557.pdf

Applying the Danish Code of Conduct for Research Integrity to your Research

- Principles of research integrity, planning phase, personal data regulation, data management, conflicts of interest, dissemination of results

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_6768b194139a455eb5d1d624c481d100.pdf

Online Profiles, Dissemination and Metrics

- Open Access publishing
- Researcher profiling – to strengthen the exposure of own research and research profile
- Research evaluation – introduction to traditional and new methods including h-index and alternative metrics
- Copyright and plagiarism

Link: https://www.campagna-robotics.com/_files/ugd/1d4f1d_d6bf0dd9954d40e695f03bfd458c99fb.pdf

Problem-Based Learning

- Problem-Based Learning (PBL) is a learner-centered approach that involves researching, applying knowledge, and integrating theory to solve a specific problem.

Link: https://www.campagna-robotics.com/files/ugd/1d4f1d_9f0a8f0b307942ddb6ca14233307850a.pdf

International Scientific Networking

- The course focuses on building global connections and collaborations within the scientific community to enhance research and knowledge exchange.

Link: https://www.campagna-robotics.com/files/ugd/1d4f1d_3d11241b35664f1b8f14d9cb55a4e93b.pdf

PROJECTS

[15/01/2022 – 15/01/2025]

Automatic Assessment of Trust in Human-Robot Interaction

Trust is essential for effective automation. In **Human-Robot Interaction**, trust becomes more complex due to the robot's physical presence alongside the operator. Current research relies on post-hoc trust measurements, which help optimize system design but don't allow for **real-time trust adjustments during tasks**. This project aims to: (i) identify **trust indicators** in industrial Human-Robot Collaboration, (ii) collect sensor data and train **machine learning models** for **real-time trust prediction**, and (iii) **adapt robot behavior** based on predicted **trust levels** to ensure efficient task performance.

This research was conducted as part of the project *RETRO: Regulating Trust in Human-Robot Interaction*, supported by the Independent Research Fund Denmark (Grant No. 1032-00311B).

Link: <https://www.campagna-robotics.com/projects>

[01/05/2024 – 30/06/2024]

Fostering Trust through Gesture and Voice-Controlled Robot Trajectories in Industrial Human-Robot Collaboration

Conducted research on **user-friendly interfaces** for **human-robot collaboration** in **Industry 5.0** manufacturing systems. Developed and tested a control framework using natural modalities—**hand gestures and voice commands**—to **guide robot** movements during maintenance tasks. The scenario involved an industrial robot transporting carbon fiber fabric to a mold, where a human operator draped the material. While both steps are automated, micromanagement tasks like maintenance checks required manual control via a smartPAD, disrupting workflow. The proposed framework enabled seamless robot control through gestures and voice, reducing interruptions and supporting operators with limited robotics experience.

Link: <https://www.campagna-robotics.com/projects>

[01/10/2023 – 29/02/2024]

Estimating Trust in Human-Robot Collaboration Through Behavioral Indicators and Explainability

The novel framework leverages **Preference-Based Optimization** (PBO) and considers three renowned **interaction parameters**: the robot's velocity profile, the separation distance between the human and the robot, and the vertical proximity to the user's head. By continuously **refining** these parameters based on **qualitative feedback** from **human collaborators**, the system **adjusts** the **robot's trajectories** dynamically. This **feedback**

was used as **ground truth** to train **machine learning models** capable of **predicting trust levels** from **human-** and **robot-related behavioral indicators**. The overall goal of this personalization is to promote a safe, ergonomic, and trustworthy human-robot interaction environment. A **chemical handling scenario** was developed as a testbed for evaluating the framework.

Link: <https://www.campagna-robotics.com/projects>

[05/2020 – 07/2020] **Cooperation Robots**

The project focuses on **optimizing collaboration** between **two robots** in a 2D industrial environment, where they **transport objects** from an **initial to a final position** while **avoiding collisions**. The robots operate on a hexagonal grid, with six possible movement directions. One robot has a malfunction, deviating from its path with probabilities of 0.2 (left) and 0.1 (right), while maintaining the desired path with probability 0.7. The objective is to develop an **optimal policy** that **minimizes the task completion time**, factoring in movement time, collision penalties, and the distance between robots. The object itself is static and does not collide with obstacles.

Link: <https://www.campagna-robotics.com/cooperation-robots>

[05/2020 – 07/2020] **Lin Kernighan Algorithm**

The **Traveling Salesman Problem (TSP)** is a classic **combinatorial optimization problem** that seeks the **cheapest route** to **visit a set of cities** and **return** to the **starting point**. It can be viewed as finding a minimum-weight Hamiltonian cycle in an edge-weighted graph. The **Lin-Kernighan (LK) algorithm** is a **local search method** for solving TSP, where it starts with an initial tour and iteratively performs k-opt moves—exchanging k edges to reduce the tour length. This process repeats until no further improvements are possible, often with randomized starting points for multiple attempts.

Link: <https://www.campagna-robotics.com/lin-kernighan-algorithm>

[09/2019 – 04/2020] **Shape-Based Grasping Techniques with Eye Tracking Device**

The loss of a hand greatly impacts autonomy in daily, work, and social activities. Current prosthetics offer limited support due to poor control interfaces and a lack of tactile feedback, hindering effective grasping. To address this, a system was developed for prosthetic hands that enables **adaptive grasping** based on **object shape**. The system extracts the **user's intent** via **EMG signals** from a Myo Armband and provides **visual feedback** using an **Eye Tracking Device** and **YOLO** for **real-time object recognition**. ROS integrates both EMG and visual data to ensure proper grasping.

Link: <https://www.campagna-robotics.com/shape-based-grasping-techniques>

[02/2020 – 03/2020] **Robothon: Beach Clean Up Challenge**

Protecting the planet from pollution is a critical challenge, with coastal cleanups being a particularly demanding task typically performed by workers. Through the Technical University of Munich (TUM), I participated in the Robothon competition, where we developed a **robotic platform** to assist in **beach cleaning**. The robot **autonomously sorted various objects** by identifying, classifying, and placing them into the **appropriate containers**.

Link: <https://www.campagna-robotics.com/robothon-beach-cleanup-challenge>

[10/2018 – 02/2019] **Atari Breakout and Supervised Learning**

A **supervised learning algorithm** applied to the famous game **Atari Breakout**.