

# **Towards end-to-end controllers for soft robots**

Thomas George Thuruthel<sup>1</sup>

<sup>1</sup> Department of Computer Science, University College London, London, United Kingdom

Soft robots come in different shapes, designs, and actuation methods. Hence, it is difficult to develop universal modelling and control strategies for these systems. Learning-based approaches can bridge this gap, but still require some prior knowledge about the system. This talk discusses research directions that can enable universal control methods for soft robotic systems by leveraging end-to-end dynamic models.