ARTI ANANTHARAMAN

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EDUCATION

Carnegie Mellon University (CMU), School of Computer Science Pittsburgh, PA
Master of Science, Robotic Systems Development (MRSD) | QPA: 4.03/4.33 May 2021
Coursework: Planning and Decision-making in Robotics; Robot Autonomy; Robot Localization & Mapping; Manipulation, Estimation, & Control; Introduction to Computer Vision

R.V. College of Engineering (RVCE) Bangalore, India
Bachelor of Engineering, Electronics and Communication Engineering | CGPA: 9.70/10 July 2019

SKILLS

Programming Languages	C/C++, Python, MATLAB
Libraries/Frameworks	NumPy, SciPy, PyKDL, OpenCV, Robot Operating System
Robotics	Motion Planning, PID Control, Optimal Control, Spatial Kinematics

PROFESSIONAL EXPERIENCE

Johnson & Johnson Redwood City, CA
Robot Software Test Automation Intern, Robotics & Digital Surgery May 2020-Aug 2020
- Defined functional requirements for robotic arm to clip & unclip bronchoscope devices and assisted in the development of a working prototype
- Wrote scripts to automate testing of faults associated with joint limit, joint velocity, gravity compensation, collision detection and autonomous navigation of a robotic bronchoscope

Robert Bosch Manufacturing Solutions GmbH Stuttgart, Germany
Robotics Software Engineering Intern June 2018-July 2018
- Collaborated in the research of dynamic multi-agent planning for scheduled deployment of robotic fleets
- Programmed work plans of collaborative robots for customized applications to fit end-user requirements

Industry 4.0 Intern June 2017-July 2017
- Programmed TwinCAT3 modules for PLC-systems, in accordance with IEC 61131-3
- Designed hardware architecture and developed software to test internal prototypes

ACADEMIC & RESEARCH PROJECTS

Augmented Reality for Minimally Invasive Surgery - MRSD Capstone Project Sept 2019-Dec 2020
Robotic surgical system built atop the da Vinci Research Kit and incorporating methods in registration, organ motion compensation, force sensing to autonomously localize liver tumors
Advisor: Dr. Howie Choset, CMU Biorobotics Lab
- Registered robot and stereo camera coordinate frames within 4 mm RMSE using Horn's method
- Developed a motion planner for robot arm to scan region of interest on silicone liver and yield 3D point cloud
- Registered 3D point cloud to ground truth within 3 mm RMSE using Iterative Closest Point algorithm
- Estimated motion frequency of silicone liver within 0.05 Hz of ground truth using Principal Component Analysis and Fast Fourier Transform
- Implemented a resolved-rate motion controller to palpate moving liver and localize embedded tumors

Planning for a High-DOF Planar Arm Aug 2020-Sept 2020
- Implemented RRT, RRT-Connect, RRT*, PRM planners for a 5-DoF arm to move from start to goal configuration
- Compared average planning times, average number of vertices generated, and average path qualities of the planners

Catch A Moving Target July 2020-Aug 2020
- Implemented A* Search Algorithm to generate a path for robot to catch a moving target within a given time interval.
- Tested the planner on maps of 4 different environments and incorporated time & memory optimization features.

Robotic Bin Picking Feb 2020-May 2020
- Implemented a manipulation system for robot arm to grasp objects using 6-DoF poses obtained from wrist camera
- Implemented RRT algorithm in task space for robot arm to transfer objects from source bin to target bin

Path Planning on Constraint Manifolds Feb 2020-Mar 2020
- Implemented RRT algorithm to generate collision-free trajectory for robotic arm to reach target configuration
- Projected C-space samples onto constraint manifold to keep end-effector in vertical orientation

Spatial Kinematics of a 7-DoF Robotic Arm Jan 2020-Feb 2020
- Computed inverse kinematics of Franka Emika robot using Jacobian transpose method
- Implemented collision detection of two oriented bounding boxes using Separating Axis Theorem

Control and Trajectory Generation of a Quadcopter Sept 2019-Oct 2019
- Developed elementary state machine to simulate quadcopter takeoff, hover and trajectory tracking
- Implemented PD controller and LQR controller to enable robot to track trajectory, and compared their performances