

Year	Degree, Board	Course, Institute	CPI/%
2015 - 2019	Graduation, BTech.	Mechatronics Engineering, Manipal Institute of Technology, KA	8.83/ ¹⁰
2012 - 2014	AISSCE, CBSE Delhi	Vasant Valley School, Delhi	95.00%

INTERESTS

Legged Locomotion, Central Pattern Generators, Rehabilitative and Assistive Devices, Nonlinear Control

ACHIEVEMENTS

- Best Rover team from Asia, 8th out of 82 teams globally at the University Rover Challenge 2017, Utah.
- Best paper presentation at the iACT-2017 conference.
- Offered INSPIRE scholarship by DST, Government of India for top 1% score in AISSCE 2014 – Declined

EXPERIENCE

- **BioRob** Dr.Auke Jan Ijspeert, Dr.Hamed Razavi, Jonathan Arreguit
École polytechnique fédérale de Lausanne (EPFL) January 2018 - Present
 - **Implementation of Walking Controller COMAN Robot(COMpliant HuMANoid Platform):**
Developed a package using OROCOS RTT and ROS frameworks for simulating experiments on walking and implemented a controller for stepping, walking and active balance for the COMAN Humanoid Robot.

[OROCOS and ROS Packages](#) [Validation through Comparison](#) [Videos](#)

- **Development of a Neuromechanical framework to study animal locomotion:**
Developed a package using ROS along with appropriate analysis tools and controllers for simulating modular tetrapoda models with neuromechanical control algorithms.

[Click here to gain access to this repository](#)

This work was supported by the Human Frontier Science Program (HFSP) for the Robotics-Inspired Biology project.

- **Autonomous Robotics Lab** Dr.Sudipto Mukherjee
Indian Institute of Technology, Delhi 2017 – 2018
 - **Development of an Underactuated Flexible Manipulator using Differential Flatness:**
Designed a 3-link and 4-link planar manipulator on MATLAB and implemented a nonlinear control theory called *Differential Flatness*, allowing the end effector on the manipulator to follow a desired trajectory with just 2 non-collinear input forces.

[Simulation demonstrating the trajectory based control of a 4-link manipulator](#)

- **Mars Rover Manipal** Dr.Y S Upadhyaya
Manipal Institute of Technology, KA 2015 - 2017
 - **Development of a Mars Rover Prototype:**
Developed a Mars Rover prototype that flaunts a modified rocker-bogie suspension, low pressure balloon tires, custom designed scientific testing mechanism, 6-DOF Robotic Arm and can run autonomously. It can traverse harsh Martian like terrain and steep gradients of approximately 1m height.
 - * [Best Rover team from Asia, 8th out of 82 teams at the URC 2017.](#)
 - **Robotic Arm Lead:**
Design a 6 DOF Robotic Arm with a payload of 6kgs to conduct tasks similar to those performed by the Curiosity Rover, such as screwing/unscrewing, drilling, pick and place, etc. along with a self adapting gripper attachment.

[URC-2017](#) [Critical Design Review \(2017\)](#) [Mars Rover Manipal](#)

PUBLICATIONS

Rajamani, D. K., E. D. Pitchika, K. S. Dhankar, and Y. S. Upadhyaya. "Design and development of a linear jawed gripper for unstructured environments." *Manipal Journal of Science and Technology* 3, no. 1 (June 2018). [\[link\]](#)

PRESENTATIONS

December, 2017 **Rajamani, D. K.**, Pitchika, E. D., Dhankar K. S., Shorewala, S., Bansal, D., & Upadhyaya, Y. S.(n.d.). Design Overview of a Planetary Exploration Rover for Unstructured Terrain. 3rd International and 18th National Conference on Machines & Mechanisms.
Bhabha Atomic Research Center

July, 2017 **Rajamani, D. K.**, Pitchika, E. D., Dhankar K. S., & Upadhyaya, Y. S. (n.d.). Design and Development of a Linear Jawed Gripper for Unstructured Environments. International Conference on Applied Sciences, Engineering & Technology. (Proceedings in Hard Copy)
Manipal Institute of Technology

March, 2017 **Rajamani, D. K.**, Upadhyaya, Y. S., & Dhankar, K. S. (n.d.). A comparative Analysis of Industrial Grade Parallel Gripper and Linear Grippers. ISAB Industrial Automation and Control TechEvent Day, ISA Bangalore.
Manipal Institute of Technology

TECHNICAL SKILLS

Programming	C++, Python, C#, MATLAB, Simulink, Embedded C, \LaTeX , Arduino, HTML, CSS
Robotics Software	ROS, OROCOS, GazeboSim, RViz
CAD & CAM	ANSYS Mechanical Workbench, ADAMS, Soliworks, CATIA V6, AutoCAD, Blender

PROJECTS

- **Obstacle detection and Path planning for a mobile autonomous robot using computer vision and fuzzy logic:** Implemented a heuristic based fuzzy logic approach for path planning through an unknown environment.
- **Traffic Detection using a Kalman Filter:** MATLAB Project to detect moving vehicles in a video feed from a traffic camera using Kalman filter and Feature detection.
- **LQR based control of a 3-link Linear Inverted Pendulum model (LIP):** Analysed the motion of a 3 link inverted pendulum on a moving base and design an optimal LQR based controller.