

# DO-GON KIM

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## EDUCATION

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### Columbia University

Sep 2023 – May 2025

*Master of Science, Mechanical Engineering, GPA: 4.065*

Relevant Coursework: Intro to Robotics, Computational Aspects of Robotics, Applied Robotics, Robot Learning, Intro to Control Theory, Digital Manufacturing, Mechatronics and Embedded Systems, Data Science, MS Projects in MechE

### New York University

Sep 2020 – Jan 2023

*Bachelor of Science, Mechanical Engineering, GPA: 3.823*

Relevant Coursework: Robotic Manipulation and Locomotion, Robotic Vision

Honors & Awards: Tau Beta Pi, National Society of Collegiate Scholars, Founder's Day Award, Dr. Morris Young Outstanding Project Design Award, Tandon Scholarship, Undergraduate Summer Research Program (UGSRP) Fellowship

## RESEARCH INTERESTS

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My past research can be categorized into three areas: **Finger Design integrated with Tactile Sensors**, **Signal Processing for Sensing**, and **Control Algorithm Development**. I have explored the design of systems that mimic the multiple sensory receptors of human touch. Moving forward, I aim to explore the design of tactile fingers and control systems that emulate human touch and realize sensing capabilities beyond the limits of human perception. Furthermore, I seek to investigate how these systems can help robots better understand and interact with their environment.

## PUBLICATIONS

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### Peer-Reviewed Publications

- [U.1] E. T. Chang\*, P. Ballentine\*, Z. He\*, **D. Kim**, K. Jiang, H. Liang, J. Palacios, W. Wang, P. Piacenza, I. Kymissis, M. Ciocarlie, "SpikeATac: A Multimodal Tactile Finger with Taxelized Dynamic Sensing for Dexterous Manipulation," *Under Review*
- [C.1] K. Zhang\*, **D. Kim\***, E. T. Chang\*, H. Liang, Z. He, K. Lampo, P. Wu, I. Kymissis, M. Ciocarlie, "VibeCheck: Using Active Acoustic Tactile Sensing for Contact-Rich Manipulation," *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS) 2025*

### Workshop Papers, Abstracts, and Posters

- [P.1] E. T. Chang\*, P. Ballentine\*, Z. He\*, **D. Kim**, K. Jiang, H. Liang, J. Palacios, W. Wang, P. Piacenza, I. Kymissis, M. Ciocarlie, "SpikeATac: A Multimodal Tactile Finger with Taxelized Dynamic Sensing for Dexterous Manipulation," *Northeast Robotics Colloquium (NERC) 2025, Cornell University*

## RESEARCH EXPERIENCE

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### Robotic Manipulation and Mobility (ROAM) Laboratory, Columbia University

May 2024 – Sep 2025

Graduate Researcher, advisor: Prof. Matei Ciocarlie

- *SpikeATac: A Multimodal Tactile Finger for Manipulation*
  - Designed experimental hardware platforms including parallel gripper and ATI sensor mounts for SpikeATac fingers, custom 3D-printed pokers, and PLA-, TPU-, or paper-based objects
  - Built a ROS2 data pipeline integrating PVDF, capacitive, and accelerometer sensors with a linear probe motion control for poking experiments to collect synchronized multimodal data and to characterize sensor sensitivity
  - Developed two real-time gripper stopping algorithms based on multimodal tactile sensing: a difference-based method using a 16-channel PVDF array, and a mean-difference threshold method using 7 capacitive sensors
  - Demonstrated stable grasping with a parallel gripper on deformable and fragile objects (egg, nori, raspberry, blueberry, strawberry, flower, origami cube), showcasing SpikeATac's capability for delicate manipulation
- *VibeCheck: Active Acoustic Sensing for Manipulation*
  - Designed hardware to enable active acoustic sensing, including gripper fingers integrated with piezoelectric sensors, isolated sensor housings for vibration damping, and PETG linkages for improved torque transmission
  - Developed an FFT-based signal processing framework involving frequency-domain analysis for feature extraction and sensor characterization using oscilloscopes and function generators to mitigate signal interference
  - Built a ROS2 control framework integrating the UR5 robot arm and parallel gripper with unified motion, grasp, and sensing control for automated data collection in classification and estimation tasks
  - Demonstrated a peg-in-hole insertion task using active acoustic sensing, achieving 90% success rates for in-distribution starting states and 50% for out-of-distribution using only acoustic tactile feedback

### Nonlinear Controls Research Group, Columbia University

May 2025 – Sep 2025

Graduate Researcher, advisor: Prof. Homayoon Beigi

- Established a control framework in C++ within ROS2 to develop learning-adaptive controller for Jetcobot

- Developed a PD controller which executes simultaneous commands across multiple joints
- Built safety stop mechanisms to prevent collisions between JetCobot arm links

**Data and innovative technology-driven Transportation Laboratory**, Columbia University Jan 2024 – Sep 2024  
Graduate Researcher, advisor: Prof. Sharon Di

- Spearheaded the development of a simulation framework using ROS2 and PyBullet for AWS DeepRacer, enabling ML model testing without physical hardware and fostering a dynamic environment for autonomous vehicle research
- Developed simulation tools for LIDAR data visualization and obstacle detection in simulation
- Built a ArUco marker detection system to accurately determine the orientation, and speed of the physical vehicle

**Control/Robotics Research Laboratory**, New York University Jun 2022 – Dec 2022  
Undergraduate Research Assistant (UGSRP), advisor: Prof. Farshad Khorrami

- Researched how to utilize ROS to read sensors from a robot and how to integrate data to build a map of an environment using gmapping algorithm, one of the Simultaneous Localization and Mapping algorithms
- Enabled Turtlebot3 Burger to detect obstacles and navigate autonomously with LIDAR, encoder, and IMU
- Investigated the accuracy of a map created by gmapping

## TEACHING EXPERIENCE

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**MECE E4601 Digital Control Systems**, Columbia University Jan 2025 – May 2025  
Teaching Assistant, advisor: Prof. Homayoon Beigi

- Topics: Sampling Theorem, z-Transform, Stability, Root Locus, Frequency Response, Controller Design

**MECE E4602 Introduction to Robotics**, Columbia University Sep 2024 – Dec 2024  
Teaching Assistant, advisor: Prof. Sunil Agrawal

- Topics: Homogeneous Transformations, Forward and Inverse Kinematics, Jacobians, Dynamics, Joint Control

**EEME E6601 Introduction to Control Theory**, Columbia University Sep 2023 – Dec 2023  
Note Taker, advisor: Prof. Nicolas Chbat

- Topics: Transfer Functions, Root Locus, Bode and Nyquist Plots, State-Space, Stability, z-Transform, LQR

## OUTREACH

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### Outreach and Engagement with Student Groups

- Guest speaker for the *Jeju Office of Education's "Global University Exploration for High School Students."* Presented research projects and mentored high school students from Jeju on research and study abroad pathways, July 2025
- Guest speaker for *Re'Generation Movement*, a non-profit organization empowering youth leadership. Presented research projects and discussed the importance of being part of an encouraging community, July 2025

## PROJECTS

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**Introduction to Robotics Project – Cable Driven Parallel Robot** Sep 2023 – Dec 2023

- Developed an adaptive velocity controller for a 4-cable-driven parallel robot, enabling dynamic speed adjustments based on the different objects to enhance safe handling
- Optimized the cable-driven system design by reducing number of cables to minimize collision issues
- Built 3D simulations in MATLAB to demonstrate motion planning in industrial settings like distribution warehouses

**Robotic Vision Project – Sheet Music Sight-Reader** Feb 2022 – May 2022

- Created a Colab-based CV pipeline that takes in the image of a sheet of music and outputs a playable music file
- Trained a model to detect a position of each note in sheet music using the YOLO algorithm with 90% accuracy
- Utilized Canny Edge Detector to find five lines in sheet music and applied a vertical slice on across the five lines to calculate an accurate position of five lines

**Senior Design Project – SYDRAULIC** Sep 2021 – May 2022

- Managed five student engineers for design, development, and testing of a hydraulic jack which allows individuals to escape safely from vehicles during flooding
- Conducted finite element modeling and analysis of a hydraulic jack-assisted car door escape system using ANSYS, evaluating deformation, stress distribution, and harmonic response of piston, cylinder, and door
- Achieved 850N of maximum force from piston, and 30 seconds for piston to be fully extended in any condition

## SKILLS

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**Programming Language:** Python, Arduino (C/C++), MATLAB, G-code, LaTeX, HTML

**Software/OS:** SOLIDWORKS, Onshape, ROS2, micro-ROS, PlotJuggler, Gazebo, PyBullet, MATLAB, ANSYS, Linux

**Machining/Tools:** 3D printing (FDM, SLA), Laser cutting, Soldering, Silicone molding, Vertical bandsaw

**Language:** English (Native or bilingual proficiency), Korean (Native or bilingual proficiency)