

Jeffin Johny Kachappilly

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EDUCATION

University of Maryland | *M.Eng. in Robotics*

College Park, MD, US | **08.2021 – 05.2023**

- Relevant Coursework: Manufacturing Robotic Software, Planning, Advanced Perception, Robot Modeling, Control Systems, Rehabilitation Robots, Deep Learning Frameworks, Hands-on Aerial Robotics.
- Cumulative **GPA**: 3.96/4.0

National Institute of Technology, Calicut (NITC) | *B.Tech in Mechanical Eng.*

Kerala, India | **07.2016 – 05.2020**

- Relevant coursework: Automobile Engineering, CAD/CAM, Manufacturing and Machine Design.

SKILLS

Programming Languages: C++, Python, Matlab

Tools & libraries: Gazebo, Solidworks, OpenCV, ROS 1, ROS 2, PyTorch, git, Docker, PX4, Arduino, ANSYS, MS Office

Controls: LQR, LQG, Kalman Filter, EKF, Impedance Control

Deep Learning Models: Neural networks, CNN, VAE, RNN, Transformers

EXPERIENCE

Graduate Research Assistant | *ROS, Arduino, C, Ardupilot (Team)*

UMD | **(09/22 – 05/23)**

- Developed **quadrotor** for NIST's First Responder Indoor Challenge (UAS 4.0), winning the competition.
- Implemented **obstacle avoidance** using Time of Flight sensors for safe navigation.
- Assisted in optimizing flight controller settings and manufacturing process.

Research Assistant for SPOT | *ROS, C++, Python (Team)*

UMD | **(01/23 – 05/23)**

- Integrated ROS packages for **localization** on Spot robot dog for **autonomous outdoor navigation**.
- Utilized a suite of advanced sensors including **GPS**, **IMU**, **LiDAR**, and **stereo cameras**.
- Investigated **various sensors** and developed algorithms for **contactless vital signs** detection for triage.

PROJECTS

[Hands-on Aerial Robotics \[LINK\]](#) | *PX4, ROS, Matlab, C++ (Individual)*

UMD | **(01/23 – 05/23)**

- Mastered quadrotor fundamentals using the **ModalAI** m500 kit: (**IMU**, **monocular** camera, 1D LiDAR).
- Introduced **FOLLOW ME** mode, enabling real-time detection and tracking of humans traveling up to **1m/s**.
- Programmed **PD** controllers for precise **yaw** and **depth** control, and used **YoloV5** model.
- Analyzed **edge cases**, identifying insights for enhancing algorithm reliability and future work.

[Anomaly Detection in video surveillance \[LINK\]](#) | *PyTorch, seaborn (Team)*

UMD | **(10/22 – 12/22)**

- Trained **Multi-Task Variational Auto-Encoder** (VAE) to generate pseudo features in **weakly supervised** setting.
- Augmented recent works which used **Attention mechanisms** with these pseudo features.
- Tested model on ShanghaiTech & UCF-crime datasets, achieving **improved AUC**: 94.21% and 83%.

[Adaptive Impedance Control \(AIC\) on the Anklebot \[LINK\]](#) | *Python (Team)*

UMD | **(11/22 – 12/22)**

- Validated existing work, where AIC strategy was used for assistive-resistive robot-aided therapy.
- Enhanced backdrivability of system by introducing **force feedback** and showcased its efficacy.
- Reduced jerk motion of **ankle trajectory** by modifying the cost function of position and actuator torque.

[First Principles of Computer Vision \[LINK\]](#) | *numpy, matplotlib (Individual)*

UMD | **(09/22 – 12/22)**

- Implemented fundamental concepts: Edge detection, **Keypoints estimation** using corners, **Optical Flow** using Lucas-Kanade algorithm, **Iterative Closest Point** using Affine Transforms and Image Stitching.
- Executed **Structure from Motion**, **Stereo vision** using **Epipolar Geometry** and depth map estimation, **Superpixel** segmentation and scene segmentation using Gaussian Mixture Model.
- Performed transfer learning-assisted **Semantic Segmentation** on VOC2007 images, with VGG16 backbone and **FCN-32** model. Pixel-wise cross entropy loss used.

[Agile Robotics for Industrial Automation Competition \(ARIAC\) \[LINK\]](#) | *C++, Gazebo (Team)* UMD | **(01/22 – 05/22)**

- Formulated a complex control system to handle **kitting** and **assembly** operations in automated warehouse.
- Manipulated robotic arms (**on linear rail and gantry robot**) using Moveit! and **AGV** using ARIAC plugins.
- Monitored environment using **cameras** and **break beam** sensor.
- Addressed **challenges** in manufacturing: sensor blackout, faulty parts, flipped parts and high-priority orders.

- Created a competitor ROS package and was **victorious** out of the 6 participating teams.

A-star implementation with non-holonomic constraints [LINK] | *Python, ROS (Individual)* *UMD | (01/22 – 02/22)*

- Designed a 2D environment with obstacles using matplotlib and implemented algorithm for a circular robot.
- Programmed an **open loop controller** in ROS and effected it on actual turtlebot3.
- Traversed the **physical map** quickly, earning a **top 5 rank** among competing teams.

Control of a Gantry Crane [LINK] | *Matlab (Individual)*

UMD | (12/21)

- Developed **LQR** controller for a crane suspending two masses to minimize oscillations.
- Derived motion equations, linearized the model, and performed controllability and observability checks.
- Deployed **Kalman filter** for state estimation and implemented **LQG**.

Design of Test Rig to characterise Braking in LHB [LINK] | *SolidWorks, ANSYS (Team)* *NIT Calicut | (07/19 – 06/20)*

- Designed a system model to match the energy dissipated during the braking of LHB coaches.
- Implemented gear system which resulted in **65% mass reduction** of test rig.
- Researched and developed a contactless system to measure the brake torque.

EXTRA CURRICULAR ACTIVITIES

- Supervised gaming stalls at Ragam (one of the largest cultural fests in India). *NIT Calicut | (2019)*
- Volunteered in Kerala flood relief campaign. *India | (2018,2019)*