

# SHARWIN PATIL

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Chicago, IL

## EDUCATION

### Northwestern University | Master of Science in Robotics

Expected Graduation: 12/2025

Chicago, IL

### Northeastern University | B.S. in Computer Engineering & Computer Science, Minor in Robotics

Graduated: 05/2024

Boston, MA

## SKILLS

**Robotics:** ROS/ROS2, Nav2, MoveIt, RViz2, Gazebo, OpenCV, Robot Kinematics, Dynamics, & Manipulation

**Software:** Embedded C, C++, Python, C#, .NET, Java, Matlab, Linux, Git, Unity, Docker, SolidWorks (CSWA)

**Machine Learning:** Computer Vision, PyTorch, CNNs, Reinforcement Learning (DQN, PPO)

## EXPERIENCE

### Locus Robotics | Planning & Controls Intern

06/2025 – Present

Remote

- Reduced mobile robots' downtime by 30% by optimizing charging behavior and battery management when routing robots

### GreenSight | UAV Robotics Engineer Co-op

06/2023 – 12/2023

Boston, MA

- Developed RTOS firmware for communications between a swarm of drones and GCS over LoRa for collecting real-time weather data
- Implemented a Hardware-Abstraction-Layer (HAL) in C for the ESP32 platform to interface with a custom LoRa chipset
- Created a custom SPI driver for the ESP32 to connect to peripherals for the drone's data collection

### Fulfil Solutions | Robotics Software Controls Co-op

07/2022 – 12/2022

Redwood City, CA

- Developed planning code in C# for high-level behavior and task assignment for up to 50 robots in a warehouse automation setting
- Composed data fetching functions to bridge C# sequencing code to MongoDB
- Optimized AGV planning and curated heuristics for maintaining the factory's health while improving performance
- Deployed factory-wide alerts and notifications for operators to react with relevant safety measures

### Doble Engineering | Software Engineering Co-op

07/2021 – 12/2021

Marlborough, MA

- Developed an external data persistence mechanism in C# running on the .NET framework for various Doble software products
- Designed and deployed a firmware installation wizard using Windows Presentation Foundation (WPF) for Doble instruments

## PROJECTS

### Open Sourced ROS2 Delta Robot

01/2025 – 03/2025

- Designed and fabricated a 3-DOF delta robot using 3D printed parts and Dynamixel motors
- Derived Jacobian for planning and executing both position and velocity trajectories
- Authored a configurable ROS 2 package to interface with any delta robot and provide motion planning and sensor telemetry

### Toasting Bread with Franka Robot Arm

11/2024 – 12/2024

- Implemented a ROS2 package to interface with the MoveIt API for sending motion requests to the Franka robot arm
- Utilized an Intel Realsense camera to identify april tag markers for the robot to interact with the scene
- Collaborated within a group of students to sequence the camera and robot with the scene elements to autonomously toast bread

### KUKA Mobile Manipulator Pick and Place Simulation

11/2024 – 12/2024

- Implemented a task-space feed-forward controller for the KUKA YouBot in Python for pick and place tasks
- Derived Jacobian for omni-directional mobile base and robotic arm to generate velocity trajectories for robot arm and the mobile base

### Automated Poker Table

01/2023 – 04/2023

- Designed an automated card shuffler and dealer with stepper motors, 3D printed parts, and sensors for detecting cards
- Developed firmware for I2C and serial communications between STM32 microcontrollers and a Raspberry Pi
- Trained a Convolutional Neural Network to classify cards for game management and software shuffling
- Earned first place for Northeastern's ECE Capstone 2023