

EDUCATION

<i>Worcester Polytechnic Institute</i>	Worcester, Massachusetts
Master of Science in Robotics Engineering (In progress)	2022-2024
■ GPA: 3.82/4.00	
<i>Sardar Patel College of Engineering (University of Mumbai)</i>	Mumbai, India
Bachelor of Technology in Mechanical Engineering	2018-2022
<i>Capstone Project: Design and Development of an Autonomous Cooking System</i>	
■ CPI: 8.95/10.00 (Class Rep)	

TECHNICAL SKILLS

- **Programming Languages:** Python, C/C++, Java, Arduino, MATLAB, Bash
- **Software:** ROS/ROS2, Gazebo, WeBots, ADAMS, SolidWorks, Creo, AUTOCAD, CURA (3D Printing), Excel
- **Important Libraries and Frameworks:** OpenCV2, Point Cloud Library, TensorFlow, OOP, Numpy, PyGame, Git, Linux/Unix, Windows
- **PLC Programming** (Representation in STL, LAD and FBD),
- **Fast Prototyping, 3D Printing, Pneumatic/Hydraulic System Design, GD&T, Control System Design, Sensor Fusion, Deep Learning, Machine Learning, Reinforcement Learning, Computer Vision (Modern and Classical)**

WORK EXPERIENCE

Void Robotics	September-December 2023
<i>Robotics Software Intern</i>	3 Months
■ Enhanced autonomous delivery robot navigation accuracy by integrating NMEA and F9P GPS systems.	
■ Leveraged Micro ROS for real-time communication, improving control and system reliability.	
■ Collaborated effectively in a cross-functional team, contributing to the overall performance of the project.	
The Innovation Story, Mumbai	October-December 2021
<i>Robotics Teaching Intern</i>	2.5 Months
■ Devised a robotics syllabus for 8th-10th graders in local schools including requisite physics and math along with robotics-specific knowledge.	
■ Designed and fabricated a modular mobile pick and place robot for teaching purposes.	
Bridgestone India Pvt Ltd	June-July 2021
<i>Mechanical Execution System (MES) Intern</i>	1.5 Months
■ Hands-on training experience in MES with emphasis on principles of IOT and Industry 4.0	
■ Prepared an internship report to be utilized for training future interns.	

PROJECTS

Grasp Generation using top surface Point Cloud data and Robot Control Using Visual Servoing	September-October 2023
■ Utilized Point Cloud library and ROS2 to process data from a simulated RGB-D camera, generating top surface point clouds for objects on a table.	
■ Applied grasp quality metrics and grasp matrix to a parallel jaw gripper to synthesize effective grasping points for objects.	
■ Implemented robot control using the analytical Jacobian for a 2D RRBot, and feedback using image features to achieve the generated grasp	
RRT Based Motion Planner for pick and place on a UR5e robot	March-April 2023
■ Implemented a MATLAB simulation of RRT based motion planning on UR5e in the presence of obstacles	
■ Used the robotics toolbox for importing an accurate robot model	
■ Sampled points in Cartesian space and used inverse kinematics for pose estimation to perform collision detection	
Parallel Parking Motion Planner using Hybrid A*	February-March 2023
■ Developed a 2D environment from scratch using PyGame to simulate a car moving in an environment with obstacles	
■ Enabled convex polygon collision detection using separating axis theorem and introduced optimizations to speed up calculations	
■ Developed a kinematically consistent motion planner to park the car between 2 obstacles using hybrid A*	
Deep Q-Learning based model for controlling a car in a 2D Environment.	November-December 2022
■ Collaborated in a team of 4 to implement a deep reinforcement learning model involving driving a car on a racetrack with other cars present.	
■ Used TensorFlow and OpenAI Gym to build the model and generate the environment respectively.	
■ Devised a novel exploration strategy using q-values as probability measures for each action.	
Pick and place on a UR5e robot using ROS.	October-December 2022
■ Collaborated in a team of 5 to implement pick and place operations on a real UR5e robot.	
■ Used the ur_robot_driver ROS library to interface with the robot through a static network address.	
■ Derived the forward kinematic equations from scratch using PoE notation and used Newton-Raphson method to numerically solve inverse kinematics.	
Design and development of an autonomous cooking system (Undergraduate Capstone Project)	January-June 2022
■ Collaborated in a team of 3 to build a 5 DOF Robot arm from scratch including CAD Modelling, Electronic circuits, and Control algorithms along with subsidiary systems to enable cooking actions.	
■ Applied different software at various levels of development including SolidWorks, Ansys and WeBots (to simulate the system along with the control algorithm).	

ACHIEVEMENTS

- **Publications:**
 - Mepani, M. M., Gala, K. B., Mishra, T. A., Bhole, K. S., Gholave, J., & Daingade, S. (2022). Design of robot arm for domestic culinary assistance. *Materials Today: Proceedings*, 68, 1930-1945.
 - Bhoir, A. A., Mishra, T. A., Narayan, J., & Dwivedy, S. K. (2023). Machine Learning Algorithms in Human Gait Analysis. In *Encyclopedia of Data Science and Machine Learning* (pp. 922-937). IGI Global.
- **DD-Robocon:** Collaborated in a team of 20 students to earn National Rank 1 in Round 1 in 2019 and 2021. Rank 9 attained in the Final Round in 2019 and 2020, special prize for Best Solution Idea, 2019.
- **National Engineering Olympiad:** National Rank 8 in 2019.
- **NPTEL course 'Speaking Effectively':** Top 1% Nationally
- **AMCAT:** 99th Percentile in Quantitative Ability (Advanced), 97th Percentile in Logical Ability
- **FTC (FIRST Tech Challenge):** Achieved Rank 3 in the National robotics competition and participated in the Asia-Pacific Invitionals in 2015 held at Sydney, Australia.