



# Praveen Ramanujam

## Curriculum Vitae

*"Satisfaction lies in the effort, not in the attainment, full effort is full victory." - Mahatma Gandhi*

### Education

- 2011–2014 **Masters of Computer Science**, Bonn-Rhein-Sieg University of Applied Sciences, Bonn, Germany, GPA – 1.6.  
German Grading System
- 2003–2007 **Bachelors of Engineering**, Tamilnadu College of Engineering, Tamilnadu, India, GPA – 8.1.  
Specialized in Electronics

### Masters Thesis

- Title *Robust Navigation in Unstructured Environments*
- Supervisors Professor Paul G.Ploeger & Professor Erwin A.Prassler
- Description This thesis was based on a hypothesis a dynamic model of a mobile robot can improve robot navigation in unstructured environment and the motor model itself can act as sensors which can detect contact with environments.

### Experience

#### Vocational

- Oct2014– **Robotics Engineer**, MUJIN INC, Tokyo, Japan.
- Present Laser-worker Project

- Real world implementation of AI algorithms.
- GCode(Industrial Language) parsing in python.
- Understanding Robotics Industrial Standard.

- Feb2014– **Research Intern**, LOCOMOTEC, Bonn, Germany.

- Sep2014 Android applications and software interfaces to embedded devices

- Sept2013– **Research Intern**, DLR, Munich, Germany.

- Jan2014 Integration of Bullet physics engine to simulation software

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Sept2011– **Teaching Assistant**, BONN-RHEIN-SIEG UNIVERSITY OF APPLIED SCIENCES,  
Feb2014 Bonn, Germany.

- Robot Manipulation.
- Introduction to Robotics.
- Statistical Analysis.

June2007– **Automotive Software Engineer**, ROBERT BOSCH, Coimbatore, India.

- Feb2011
- Communication Interfaces such as CAN.
  - Accurate sensor model development for cost reduction.
  - Understanding of automotive development.
  - First support for Japanese customers in passenger market.

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## Extras

- 2014 Master Thesis Grant  
2014 DAAD commitment award for Bonn region

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## Computer skills

- Intermediate JAVA, Lisp, R  
Advanced Python, C++, Matlab

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## Past Research

- Preliminary A Software Framework for Simulation of Mobile Robot Models.  
Advanced Motion Planning of Mobile Manipulators in Unstructured Environments under a set of Constraints.