

Kautilya Chenna

Skills

Languages: C++, Python, MATLAB.

Tools: PCL, ROS, Gazebo, OpenCV, Tensorflow, Keras.

Robots: KUKA LBR4+, Rethink Robotics Baxter, SimLab's Allegro Hand, Quanser HD2.

Experience

Omron Research Center of America (ORCA)

Motion Planning Engineer

November 2018 – Present

- Motion Planning and Grasp Planning for Random Bin Picking
- Trajectory Optimization and more stuff. Ssshhhhh....

Learning Lab for Manipulation Autonomy (LL4MA Lab), University of Utah

Graduate Research Assistant

August 2016 – 2018

- Built a fast object detection and tracking pipeline, which is used by multiple teams in the Lab.
 - Implemented Grasp Controllers and end-to-end Grasping Pipelines with motion planning and execution.
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Education

University of Utah, Salt Lake City, Utah

Master of Science in Robotics

Aug 2016 – Aug 2018

BMS College of Engineering, Bangalore, India

Bachelor of Engineering in Mechanical Engineering (Robotics)

Sept 2011 – May 2015

Relevant Coursework: Probabilistic Modeling, 3D Computer Vision, Artificial Intelligence, Motion Planning, Machine Learning, Convex Optimization, Robotics, Robot Control and System Identification.

Publications

“Planning Multi-Fingered Grasps as Probabilistic Inference in a Learned Deep Network”; Qingkai Lu, **Kautilya Chenna**, Balakumar Sundaralingam, Tucker Hermans; *International Symposium on Robotics Research (ISRR)*, 2017. [[PDF](#)] [[CODE](#)]

Selected Projects

Others: Motion Planning: TrajOpt, RRT and Variants, RealTime RRT*; Image Segmentation with GMM, Image De-noising using MRF;

Contact Information

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Links

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