

SUMMARY

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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.

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;

LINKS

Website: <https://chenna.me> **Linkedin:** [kautilyachenna](#) **Github:** [hashb](#)