Kautilya Chenna

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Summary

lorem ipsum

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

Last updated: December 23, 2019 • Typeset in XeLaTeX
https://chenna.me/resume