

Lara Zlokapa Design Portfolio

MIT (M.S., 2022), UC Berkeley (B.S., 2020)
Mechanical Engineering

PROJECT HIGHLIGHTS



Modular, Sensorized Robotic Hand Design

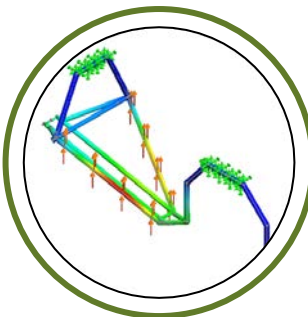
Four cable-driven robotic hands made to pick up eggs, tighten screws, pour water, and cut paper with scissors.

RSS 2021, Master's Thesis (MIT).

Mechanical Gripper for Quadriplegics

Mechanically actuated device to assist people with reduced hand function in grasping objects.

Global Product Development (UC Berkeley).



Human Powered Speed Vehicle

Aerodynamic, recumbent bicycle designed to achieve 70 mph at the World Human-Powered Speed Challenge.

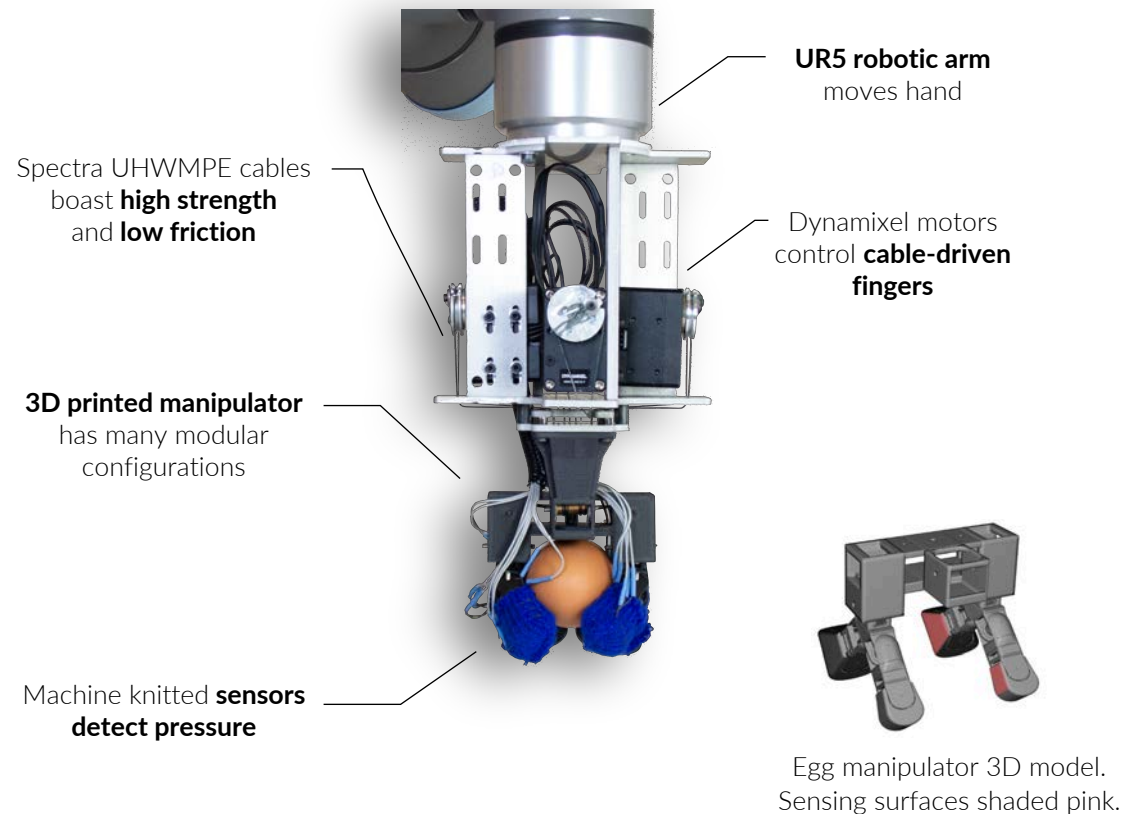
President, Human Powered Vehicles Club (UC Berkeley).

MODULAR, SENSORIZED ROBOTIC HANDS

Masters Thesis under Profs. Wojciech Matusik and Pulkit Agrawal, MIT

Aug. 2020 - Present

Egg-Grasping Manipulator



My Contribution

I designed modular, parametrized, sensorized, cable-driven robotic manipulators with automated assembly (via grammar production rules) and manufacturing. I programmed open-loop controls in Python to perform tasks.

Additional Models



MODULAR, SENSORIZED ROBOTIC HANDS

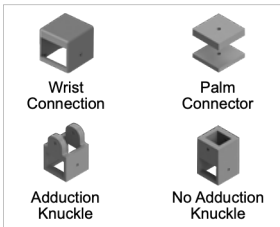
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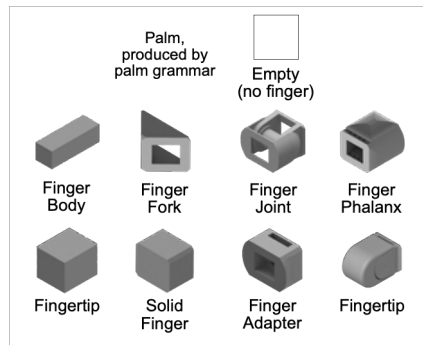
Modular Approach

To overcome time-consuming and trial-and-error process of designing robotic hands, I created a pipeline to generate modular, parametrized, sensorized robotic manipulators. With this, users can develop new manipulators in minutes.

PALM COMPONENTS

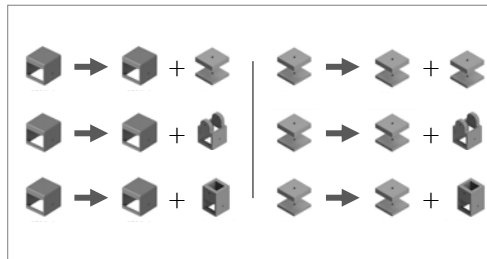


FINGER COMPONENTS

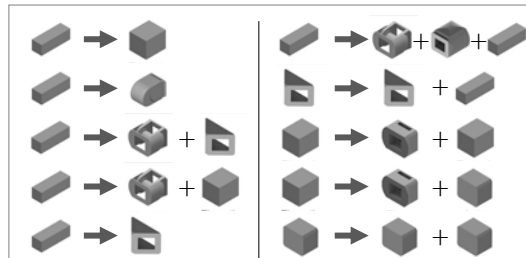


I designed a "Lego kit" of subcomponents that merge virtually to create any cable-driven hand.

PALM ASSEMBLY RULES

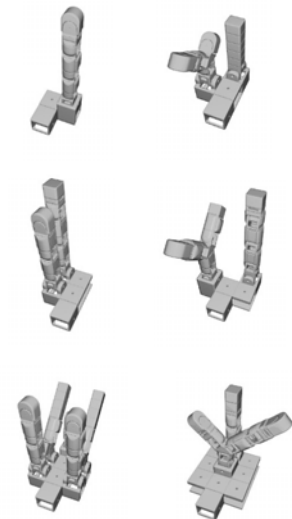


FINGER ASSEMBLY RULES



The user applies assembly (grammar production) rules on subcomponents to form the "palm" then "fingers".

SAMPLE CONFIGURATIONS



I designed the components and assembly rules to always ensure manufacturability and valid cable pathways.

MODULAR, SENSORIZED ROBOTIC HANDS

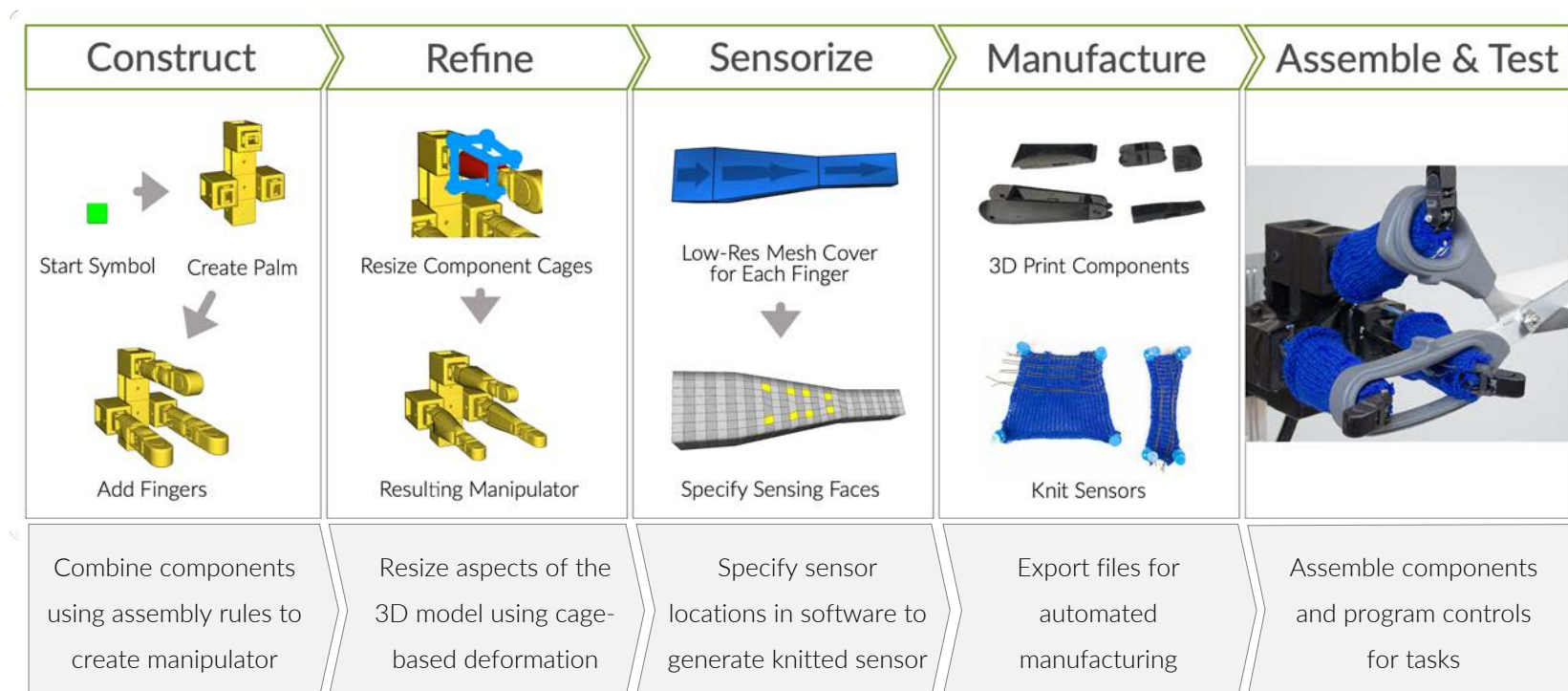
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Aug. 2020 - Present

The Design Pipeline

Below is an overview of the streamlined design process. For videos of the manipulators performing tasks, please see my website:

https://lara-z.github.io/robotic_hand.html

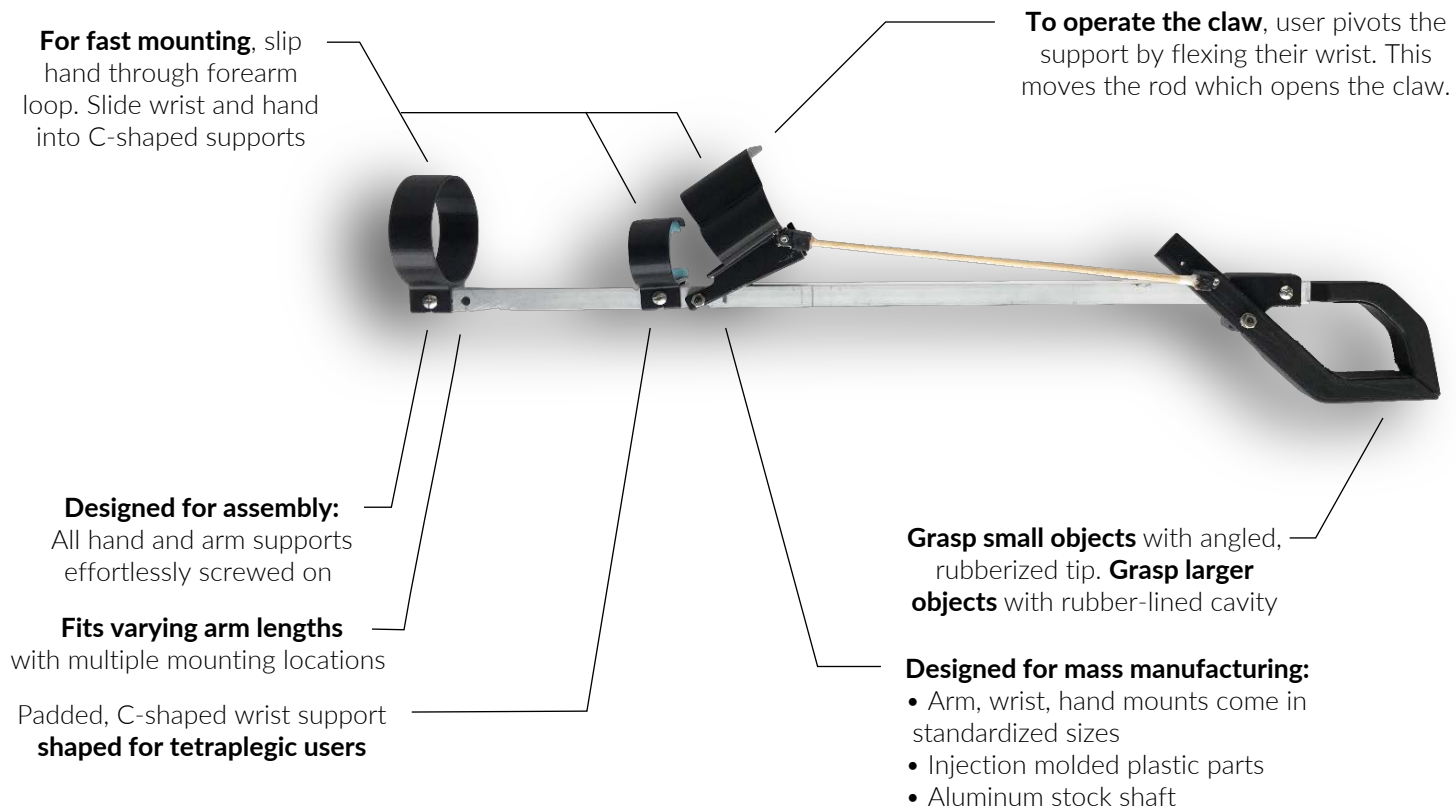


Aspects of research were published in [An End-to-End Differentiable Framework for Contact-Aware Robot Design](#) (RSS 2021).

MECHANICAL GRIPPER FOR TETRAPLEGICS

Global Product Development Class and EnableTech Club, UC Berkeley

Spring 2018, Spring 2019



My Contribution

I led a team of three (2019 class) and worked in a team of four (2018 club) to design and build a durable, affordable, easy-to-use, mass manufacturable gripper device for a tetraplegic person with limited hand dexterity in a wheelchair to pick items from floors and shelves. We performed user testing with three tetraplegic individuals.

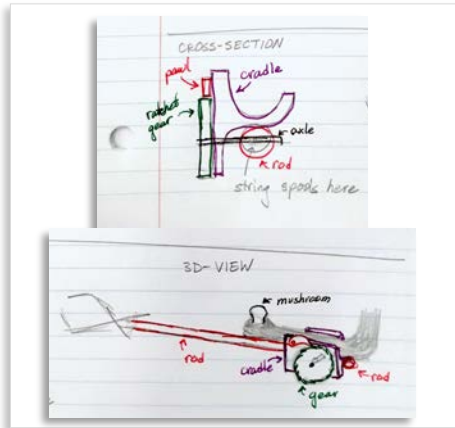
MECHANICAL GRIPPER FOR TETRAPLEGICS

Global Product Development Class and EnableTech Club, UC Berkeley

Spring 2018, Spring 2019

Prototype Development

SPRING 2018



Brainstorm sketch



Laser cut test shapes of different claw and ratchet-and-pawl actuation



Spring 2018 final prototype developed with user testing

SPRING 2019



Change to wrist actuation and re-design for mass manufacturability



3D printed wrist and arm support sizes tested with various users



Spring 2019 final prototype

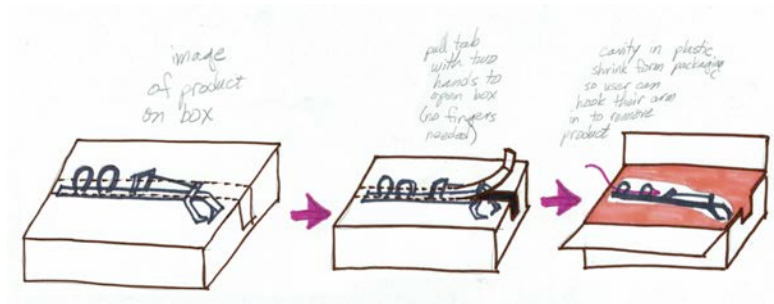
MECHANICAL GRIPPER FOR TETRAPLEGICS

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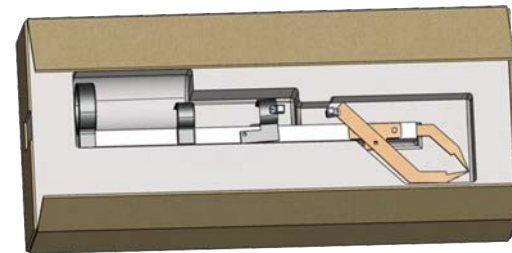
Spring 2018, Spring 2019

Product Packaging

I designed the product packaging for tetraplegic users to open independently without additional tools or other aids.



A SolidWorks model reveals the box interior. Padding inside the box holds the product in place for easy removal.



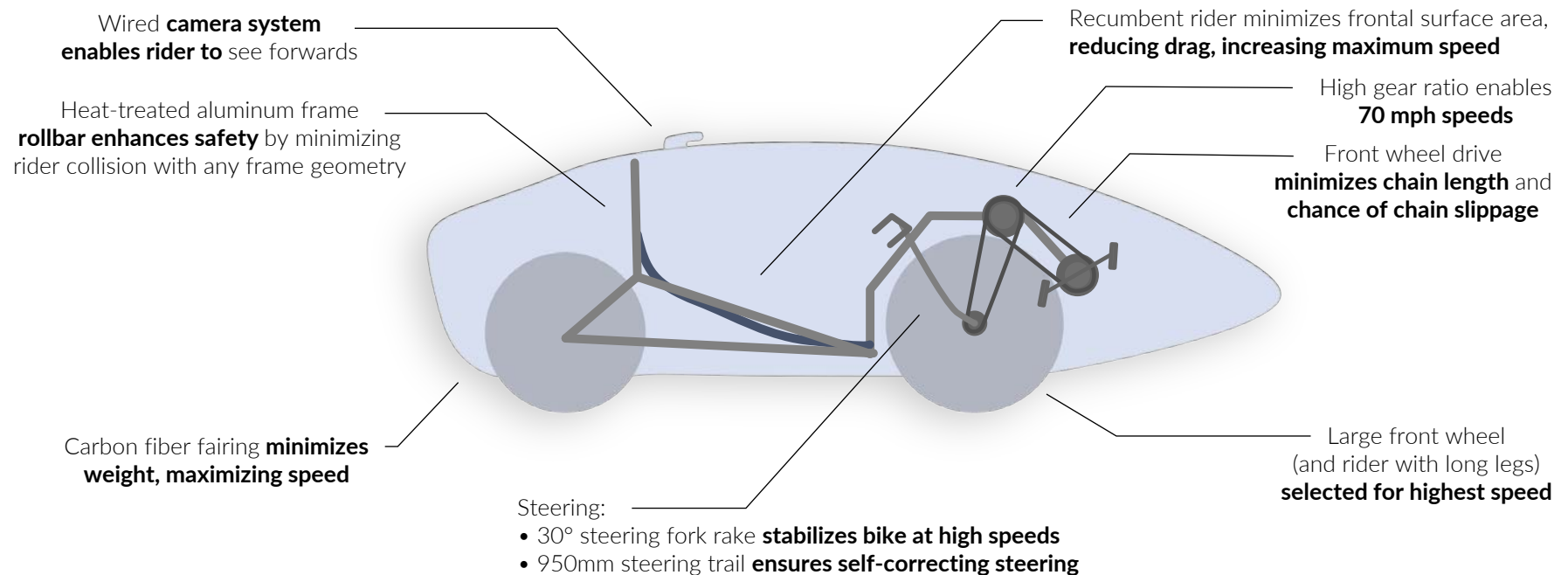
A scaled down laser cut box demonstrates the frustration free opening method.



HUMAN-POWERED SPEED VEHICLE

President, Human Powered Vehicles Club, UC Berkeley

May 2018 - Aug. 2019



My Contribution

As president of the club, I led a team of thirty engineers in the design, testing, and manufacturing of a human-powered vehicle with a goal speed of 70 mph (no motor!).

Due to Covid-19, the vehicle was never completed or raced after I left the club.

HUMAN-POWERED SPEED VEHICLE

President, Human Powered Vehicles Club, UC Berkeley

May 2018 - Aug. 2019

Initial Design



We created an adjustable wooden model to determine the optimal bike geometry (seat angle, pedal location, wheel size, chassis width, etc.) for our rider.

Once we finalized our model, we quickly converted it to a plywood prototype for the rider to ride to double check our dimensions and test our drivetrain design.



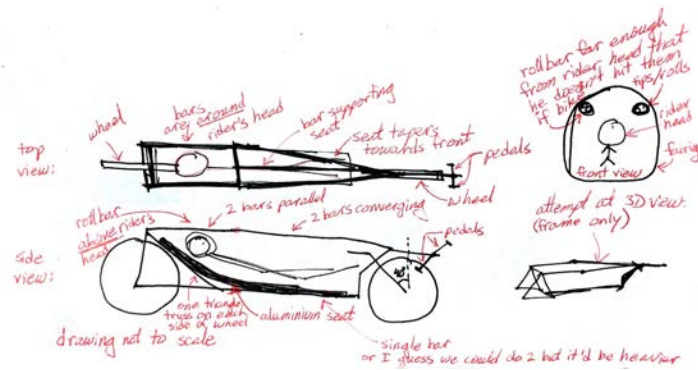
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Frame Design

I led a sub-team of five in the design, testing, and manufacturing of the vehicle's aluminum frame. The frame shape was inspired by previous bike designs and stress simulated in SolidWorks with guidance from Ford and GM.



A sketch of an intermediate frame design



We created a PVC pipe mock-up to ensure that the dimensions were correct.



With guidance from Ford and GM, I simulated stress and deformation in SolidWorks for diverse collision scenarios based on impulse momentum calculations.

ABOUT ME

Since learning how to laser cut,
I have created countless presents for my
friends and family.



I enjoy connecting with people outside the U.S. and
speak some French, German, and Serbo-Croatian (the
language of the Balkans).



When I'm not working on my latest design project, you can find me swing
dancing, hiking, biking, baking, drawing, painting, or swimming.



A few of my laser cut projects at top: trick box with hidden locking mechanism (3 photos), trinket box with living hinge, clock.

Lara Zlokapa

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