

ADITYA PATIL

📞 9011036943 ✉ patiladitya1309@gmail.com 🔗 www.linkedin.com/in/aditya-patil-13207b201/ 🏠 maker-ATOM

ROBOTICS ENGINEER

Robotics System Designer specialized in designing control software for **Autonomous Mobile Robots** and **Manipulators** utilizing ROS. My expertise lies in Sensor-Integration and Perception for Autonomous Robot and motion control for Manipulators.

EDUCATION

Pune Institute of Computer Technology, Pune

Aug 2020 – July 2024

Bachelor of Engineering in Electronics and Telecommunication

GPA: 9.04/10

TECHNICAL SKILLS

Languages : Python, MATLAB

Technologies / Framework : ROS, Sensor integration, Swarm Intelligence, Gazebo, Rviz

Computing Environments : Linux, Raspberry Pi

Design & Manufacturing Tools : KiCAD, Fusion 360

EXPERIENCE

PICT Robotics

Apr 2021 – Aug 2023

Lead Robotics System Designer

Pune, Maharashtra, India

- Led a team of 4 to design and develop modular code-base to semi-automate ABU Robocon 2023 Robots using **ROS**.
- Introduction of **custom ROS message** to tackle unacknowledged methodology in transmitting motor parameters in ROS.
- Insertion of sync packets in serial communication between ESP32 and Raspberry Pi for synchronization.
- Utilized **sensor integration** to enable precise robot **localization**, integrating data from an Inertial Measurement Unit and Optical Mouse Sensor for accurate odometry.
- Resolved ESP32 pin count limitations by crafting a **Motor Controller HAT** using Atmega328p micro-controller, communicating via I2C protocol for each Swerve pod.
- Developed a low-cost **Swerve Drive-train** for Robocon robots through design for manufacturability using **CNC Milling** and **Sheet Metal** techniques.
- Formulated locomotion equations for an Analog Joystick-controlled **Differential Drive Train** using Dual-Core capabilities of ESP32.
- Implemented rotary encoder-based PID control on **STM32** micro-controller to evaluate both three-wheel holonomic and four-wheel mecanum drives.
- Crafted custom mounts and holders in Fusion 360, optimized for **3D printing** and tailored for ABU Robocon 2022 Robots.

Kanan Park

Apr 2022 – Jun 2022

Electronics Engineer (Intern)

Pune, Maharashtra, India

- Designed control software, utilizing **Teensy** micro-controller as the master to interface with the RC transmitter, and employing Arduino Nano as a slave to manage PID systems for individual swerve pods.
- Established communication protocols between Arduino Nano and Teensy using MAX485 (TTL to RS485), implementing an acknowledge symbol for synchronized transmission.

PROJECTS

Mapping and Navigation with TurtleBot3 | ROS, Mapping, Localization, Navigation, Python | [Git](#)

Apr – Jul 2023

- Executed robotics concepts encompassing Mapping, Localization, Path-Planning, and Navigation, further enriching familiarity with the ROS environment.
- Developed a Particle filter from the ground up, employing a random uniform pose distribution for particles. Transformed the robot's LaserScan data based on particle origins, retaining or discarding data within a predefined threshold.
- Conducted a performance analysis, comparing **Lidar performance** with 360 samples against 6 samples.

SPARK - A 4DOF Ros based Robotic Arm | ROS, Inverse and Forward Kinematics, Python | [Git](#)

Feb – Mar 2023

- Designed a 4 DOF robotic arm in the **ROS** environment, concurrently advancing robotic mathematical concepts such as Forward Kinematics (FK), Inverse Kinematics (IK), and Trajectory planning.
- Enhanced expertise in crafting **Gazebo**-based simulation environments for testing and applying robotics mathematical principles.

CERTIFICATIONS

Modern Robotics: Foundations of Robot Motion | [Link](#)

Aug 2023

Modern Robotics: Robot Kinematics | [Link](#)

Sept 2023

OPEN SOURCE

Cytron Motor Driver | [Link](#)

May 2023

- A custom library to interface with Cytron Motor Drives which utilizes PWM-DIR and PWM-PWM technique to drive DC motors.
- Optimized codebase for Espressif boards, notably ESP32, addressing **multiplexed PWM channels**.
- Introduced an additional parameter to fulfill ESP32's channel demands, while ensuring seamless **backward compatibility** by setting the parameter to its default state.