

Omey M. Manyar

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Research Interest

Robot Learning; Motion Planning; Physics-based Simulation; Reinforcement Learning; Inverse Reinforcement Learning; Computer Vision

Education

University of Southern California <i>Ph.D. in Mechanical Engineering</i>	May 2021 – Present Los Angeles, CA
University of Southern California <i>Master of Science in Mechanical Engineering</i>	Aug. 2019 – May 2021 Los Angeles, CA
National Institute of Technology Karnataka <i>Bachelor of Technology in Mechanical Engineering</i>	Jul. 2012 – May 2016 Surathkal, India

Experience

Graduate Research Fellow <i>Advisor: Dr. S. K. Gupta. Realization of Robotics Systems Lab, USC</i>	May 2021 – Present Los Angeles, CA
<ul style="list-style-type: none">Devised a learning methodology to model expert behavior from sparse demonstrations for sequential planning problems for an autonomous agentDeveloped a framework to generate physics-informed synthetic images for training a ResNet-50-based segmentation model in Pytorch to detect wrinkles and folds in a sheet. Link: code and datasetWorked on robotic manipulation of compliant objects (sheets) by training differentiable simulators	
Graduate Research Assistant <i>Advisor: Dr. S. K. Gupta. Center for Advanced Manufacturing, USC</i>	Jan. 2020 – May 2021 Los Angeles, CA
<ul style="list-style-type: none">Project lead for development of a multi-robot system for automation of composite sheet layup in collaboration with ARM Institute, Lockheed Martin and Boeing IncDevised a multi-constraint sheet grasping planner for robots using a high fidelity physics based simulatorIntegrated multiple software modules developed in C++, Java and Python with ROS to accomplish a system that reduced cycle time by 30%	
Automation Technologist <i>Rolls-Royce Plc.</i>	Jan. 2018 – Jul. 2019 Singapore
<ul style="list-style-type: none">Seconded from Nanyang Technological University for leading the technological development in advanced robotics at the manufacturing facility of Rolls RoyceSpearheaded the deployment of an AI-based smart predictive tool for surface finishing processesDeveloped a collaborative robotic solution that improved Cpk value of filleting operations to 1.98	
Graduate Engineer <i>General Motors India Pvt. Ltd.</i>	Aug. 2016 – Jul. 2017 Bengaluru, India
<ul style="list-style-type: none">Streamlined robotic welding process in the body shop unit of the manufacturing facility of GM IndiaDesigned an investment forecasting tool with savings of 25% for Global Vehicle Development Program at Level 0Formulated a dealership improvement strategy, focusing towards customer satisfaction in the west zone of GM India	
Summer Undergraduate Researcher <i>Advisor: Dr. Howie Choset. Biorobotics Lab, Carnegie Mellon University</i>	May 2015 – Aug. 2015 Pittsburg, PA
<ul style="list-style-type: none">Designed a compliant gripper based on pseudo-rigid body modelling technique for snake robots	

Awards and Recognitions

- Best Conference Paper Award. *Won the conference wide best paper award at the 42nd ASME's IDETC-CIE Conference 2022*
- Viterbi Graduate School Fellowship. *Recipient of the Viterbi Graduate School Fellowship awarded to selected Ph.D. students by the Viterbi School of Engineering, USC*
- Academic Excellence Award. *Given to the best outgoing Master of Science student by the Aerospace and Mechanical Engineering Department at the Viterbi School of Engineering, USC*
- National Science Foundation Travel Award. *Awarded at ASME MSEC Conference in 2022 and 2021, ASME IDETC-CIE 2022 and 2021*

List of Publications

- **Omey M. Manyar**, Junyan Cheng, Reuben Levine, Vihan Krishnan, Jernej Barbic and Satyandra K. Gupta. (November 22, 2022). Physics Informed Synthetic Image Generation for Deep Learning based Detection of Wrinkles and Folds. *ASME. Journal of Computing and Information Sciences and Engineering*. doi: <https://doi.org/10.1115/1.4056295>
- **Omey M. Manyar**, Junyan Cheng, Reuben Levine, Vihan Krishnan, Jernej Barbic and Satyandra K. Gupta. Synthetic Image Assisted Deep Learning Framework for Detecting Defects During Composite Sheet Layup. *ASME IDETC-CIE Conference, St. Louis, MO, USA, August 2022. Best Paper Award*
- **Omey M. Manyar**, Alec Kanyuck, Bharat Deshkulkarni and Satyandra K. Gupta. Visual Servo-Based Trajectory Planning for Fast and Accurate Sheet Pick and Place Operations. *ASME MSEC, Purdue University, IN, USA, June 2022*
- Yi-Wei Chen, Rex Jomy Joseph, Alec Kanyuck, Shahwaz Khan, Rishi Malhan, **Omey M. Manyar**, Zachary McNulty, Bohan Wang, Jernej Barbic, and S. K. Gupta. A Digital Twin for Automated Layup of Prepreg Composite Sheets. *ASME Journal of Manufacturing Science and Engineering*, September 2021. <https://doi.org/10.1115/1.4052132>
- **Omey M. Manyar**, Jaineel Desai, Nimish Deogaonkar, Rex Jomy Joesph, Rishi Malhan, Zachary McNulty, Bohan Wang, Jernej Barbic, and S. K. Gupta. A Simulation-Based Grasp Planner for Enabling Robotic Grasping during Composite Sheet Layup. *IEEE's International Conference on Robotics and Automation, Xi'an, China, May 2021*. <https://doi.org/10.1109/ICRA48506.2021.9560939>
- Vigneashwara Pandiyana, Tegoeh Tjahjowidodo, Wahyu Caesarendra, **Omey M. Manyar** and David Then. In-process virtual verification of weld seam removal in robotic abrasive belt grinding process using deep learning. *Robotics and Computer Integrated Manufacturing Journal, Volume 57, June 2019*. <https://doi.org/10.1016/j.rcim.2019.01.006>
- Srinivasan Lakshminarayanan, **Omey M. Manyar**, Domenico Campolo. Toolpath Generation for Robot Filletting. Advanced Surface Enhancement. INCASE 2019, Singapore. https://doi.org/10.1007/978-981-15-0054-1_28

Projects

- Multi-Robot Cell for Automation of Composite Layup** | Project Link Nov. 2020 – Sep. 2021
- Developed a multi-robot cell accomplishing sheet grasping/manipulation, sheet transport, sheet heating and sheet draping task
 - Developed vision-based defect detection system for contingency planning for robotic manipulation of sheet
 - Work was done in collaboration with ARM Institute and Lockheed Martin
- Human-Robot Teaming for Sheet Manipulation Task** | Video Link Jan. 2020 – Oct. 2020
- Developed a hybrid cell demonstrating the use of robots as assistants in sheet manipulation tasks on an industrial application
 - Integrated multiple software modules developed in C++, Java and Python with ROS to accomplish a system that reduced cycle time by 30%
- COVID-19 Disinfection Robot- ADAMMS-UV** | Forbes Link, Viterbi News Link Apr. 2020 – May 2020
- Extended a mobile manipulator platform to perform deep UV disinfection of indoor environments autonomously
 - Examined varied methods that can be deployed for sterilizing surfaces exposed to the coronavirus

Technical Skills

Programming: Python, C/C++, Java, MATLAB
Libraries and Frameworks: PyTorch, Tensorflow, OpenAI Gym, ROS MoveIt, OpenCV, Open3D
Middleware: Robot Operating System
Simulators: VegaFEM, WeBots, Gazebo, Unity, MuJoCo
Robots: KUKA LBR iiwa, ABB, UR5, Yaskawa
Developer Tools: Git, Docker, CUDA

Mentorship and Service

Viterbi CURVE Fellowship Mentor: Mentored Undergraduate CURVE Fellowship Recipients
Reviewer and Session Chair: RAL (2023), ICRA (2023, 2022), IDETC-CIE (2022)