

Sambad Regmi

Curriculum Vitae

Research Interests

- Theory Data analysis; Experiment design; Human biomechanics; Kinematics and dynamics of robots and robotic manipulators; Manipulator design; Rehabilitation robotics; Robotics and mechatronics (alphabetical order)
- Application Control applications such as impedance control; Data acquisition system; Motors, motor drives, sensors, and controller systems; real-time systems; Rehabilitation robotics; Robotics and mechatronics (alphabetical order)

Summary

My research interests mainly lie within the field of: (alphabetical order)

- Data Acquisition and Analysis of Human Experiments
- Human-Human and Human-Robot Interaction
- Human Neuromechanics
- Kinematics and Dynamics of Robotic Manipulators as well as Human Arms
- Rehabilitation Robotics
- Robotics and Control

Education

- Present **Ph.D, Mechanical Engineering**, *Missouri University of Science and Technology*, Rolla, MO, (Expected completion: May 2022, Current GPA: 3.933).
Doctoral Thesis Title: “Development of an Interactive Robot for Overground Physical Human-Robot Interaction”
Project: “Human Arm Impedance Modulation during Overground Physical Interactions” (*funded by National Science Foundation*)
Advisor: Dr. Yun Seong Song
- Jun 2016 **B.E, Mechanical Engineering**, *Visvesvaraya Technological University*, Bangalore, India, (Percentage: 85%).

Professional Experience

- Aug 2017 – present **Graduate Research Assistant**, *Missouri University of Sci. and Tech.*, Rolla, MO.
- Designed and developed robotic manipulator for physical human robot interaction experiments; Selected required hardware and software for the robot; and, currently trying to implement various force, position, and velocity control strategies on the robot
 - Developed a “dynamics” simulator of a robotic manipulator using Lagrangian method; estimated the friction/damping of rotational joints, and verified its accuracy using the effective inertia estimate; developed a method to estimate the output impedance of a manipulator using the robotic simulator
 - Currently selecting a data acquisition and analysis technique for experiments involving our robot

- Will be designing and conducting a human-robot interaction experiment, including acquiring an IRB approval, recruiting and interacting with the participants, preparing and maintaining the experiment setup, collecting and analyzing the data, and reporting results

- Jun 2016 – **Quality Assurance and Maintenance Engineer**, *Nepal Health Research Council*, Nepal.
 Jun 2017
- Involved in solving various issues related to the equipment for ECG and Spirometry tests that were used in project “Prevalence of Chronic Diseases in Nepal”
 - Coordinated with health workers and patients for smooth and effortless use of the devices

Publications

- [1] **Regmi, S.**, Song Y. S., “Design methodology for robotic manipulator for overground physical human-robot interaction”, *ASME Journal of Mechanisms and Robotics*, **12**(4), p. 041002, 2020.
- [2] **Regmi, S.**, Song Y. S., “Estimation of Endpoint Impedance of a 2D Parallel Manipulator using Numerical Simulation Experiment”, *ASME International Mechanical Engineering Congress and Exposition*, **Vol. 84522**, American Society of Mechanical Engineers, 2020.

Conference Abstract

- [1] Presented a poster “Design Methods for Robots for Overground Physical Interaction” at 41st IEEE Engineering in Medicine and Biology Conference (EMBC 2019), Berlin, Germany.

Awards

- Nov 2020– **John W. Claypool Fund for Medical Research**, *Received student research funding to advance research on human-human and human-robot interaction at Missouri University of Science and Technology.*
 Apr 2021
 Jul 2012– **COMPLEX Scholarship Scheme 2012, Embassy of India**, *Got selected through an open competition to pursue BE (Mech.) in India.*
 May 2016

Teaching and Mentoring Experience

- Jan 2020 – **Graduate Teaching Assistant**, *Missouri University of Sci. and Tech., Rolla, MO.*
 present
- Provided guidance during lab sessions of Control System Laboratory for undergraduate seniors in understanding physical concepts of control systems
 - Assisted students in hardware implementation of control algorithms using PLC and LabVIEW software
 - Evaluated students’ performance and provided detailed feedback on conceptual understanding
 - Maintained regularly scheduled office hours to advise and assist students
 - Taught a laboratory-heavy class online during Covid-19 situation using different strategies (whichever is feasible) such as remotely accessing the hardware, using simulated environments, and making video demos
 - Experience with course management software like Canvas, and online teaching via Zoom

Skills

- Development Tools MATLAB, LabVIEW, SOLIDWORKS, Mathcad, Maplesoft, Python, PLC
 Software Tools Vicon Nexus, Kollmorgen Workbench, Microsoft Office, Latex, proCalc

Hardware Experience Motion capture system (Vicon Motion Systems), LabVIEW Real-Time and associated control systems; LabVIEW SoftMotion, LabVIEW FPGA, and other Modules; Brushless DC motors (Kollmorgen, Anahiem Automations (AA) and others); Motor drives and controllers (Kollmorgen-AKD and AA); ATI Force/Torque sensor, and controller; Data acquisition systems (RS232, NI USB6021, NI cRIO 9045 modules, and AA modules); DirectSoft PLC ; Electrocardiogram Machine; Spirometer

Relevant Courses

Coursework Control System, Discrete Neural Network Control, Introduction to Neural Networks and Application, Mechanics of Machinery, Neuromechanics of Human Movement, Statistical Data Analysis (alphabetical)

Coursera Control of Mobile Robots, Machine Learning, Python (basics)

References

1. **Dr. Yun Seong Song**

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