

Sharath Matada

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EDUCATION

- **University of California, San Diego** La Jolla, United States of America
• *Master of Science - Mechanical and Aerospace Engineering* September, 2022 - March, 2024
Relevant Coursework:
ECE276A: Sensing and Estimation in Robotics, ECE276B: Planning and Learning in Robotics, ECE271A: Statistical Learning, MAE204: Robotics, MAE207: Soft Robotics
- **National Institute of Technology, Karnataka(NITK)** Surathkal, India
• *Bachelor of Technology - Mechanical Engineering* August 2014 - May, 2018
Relevant Courses: Automatic Control Engineering, Robotic Systems
Additional Courses: [Deep Learning using PyTorch\(IBM\)](#), Model Predictive Control

PUBLICATIONS

- **Reconstruction of Robot Motion from Video**
*In preparation to be submitted to **Science Robotics***
Jingpei Lu, **Sharath Matada**, Yiyu Chen, Florian Ritzer, Quan Nguyen, Michael Yip
[Website](#)

SKILLS SUMMARY

- **Robotics:** Optimal Control, Path Planning(A*,RRT, RRT*), Model Predictive Control for Quadrupeds, Kalman Filter, Particle Filter, Visual-Inertial Extended Kalman Filter
- **Mechanical Design:** Creo, Fusion 360, Structural Analysis, DFM, DFA, Weight Optimization
- **Programming Languages:** Python,C, C++
- **Simulation:** CoppeliaSim, MuJoCo, PyBullet
- **Robotics Software Development:** ROS2
- **Others:** Linux, Arduino, Raspberry Pi, MATLAB, Labview, Git, MS Office

EXPERIENCE

- **Graduate Research Assistant, Advanced Robotics and Controls Lab, UCSD**
Oct 2022 - Jun 2023, Advisor: Prof. Michael Yip, Associate Professor
 - Worked on reconstruction of complex robot motion (specifically dancing) on a quadruped using **Model Predictive Control (MPC)**, leveraging off-the-shelf optimal control solvers
 - Successfully implemented the MPC controller on Pybullet for the Go1 robot, achieving a frequency of 400 Hz in **C++**, enabling real-time execution
 - Implemented an **Extended Kalman Filter** for the **real Go1 Hardware Platform** to enable sim-to-real transfer
- **Senior Robotics Engineer, Systemantics(Collaborative Robotic Arm Maker)**
Jun 2018 - Aug 2022, Advisor: Dr. Jagannath Raju, CTO
 - **Mechanical Design**
 - * Contributed to the development of an integrated joint design (hollow bore) incorporating strain wave gearing, BLDC motor, output and input encoders, and compact electromagnetic brakes.
 - * Formulated designs for compact spring-loaded electromagnetic brakes, optimizing the electromagnetic coil for minimal power dissipation.
 - * Engineered lightweight links and grippers for serial robots, as well as precision components for intricate mechanisms.
 - * Generated detailed engineering drawings for production, incorporating Geometric Dimensioning and Tolerancing (GDT) principles.
 - **Robot Kinematics and Dynamics**
 - * Worked on optimizing kinematic architectures of hybrid mechanisms(combination of serial and parallel linkages)for maximum dexterity and minimum inertial load on each joint
 - * Characterized the effect of joint elasticity coupled with parallel mechanisms on robot performance in task space
 - **Motion Control**
 - * Designed feedback controller and modeled friction, inertial and gravity effects
 - * Worked on flexible joint control using full-state feedback
 - **Safety for Human-Robot Interaction**
 - * Designed a disturbance observer to detect collisions with external environment to improve safety for human-robot collaboration
 - * Implemented of admittance controller for lead through programming
 - **Software Design**
 - * Designed a finite state machine and implemented a state estimator
 - * Implemented trapezoidal commutation for BLDC motor in a robot joint

COURSE PROJECTS

- **ECE276A: Sensing and Estimation in Robotics** University of California, San Diego
Winter, 2023
 - Conducted data synchronization between IMU and stereo camera image features for accurate and efficient measurements
 - Implemented EKF prediction for real-time positioning and orientation updates using SE(3) kinematics and IMU measurements
 - Developed EKF update step to correct landmark locations using Jacobian of observation model with visual observations
 - Simultaneously corrected car pose and landmark locations using observation model Jacobian w.r.t. car pose, feature locations
 - Analyzed sensitivity to motion and observation model noise and generated an environment map achieving 95% accuracy
- **ECE276B: Planning and Learning in Robotics** University of California, San Diego
Spring, 2023
 - Implemented a collision-checking mechanism for a robot's safe navigation in 3D maze-like environments towards the goal
 - Implemented and assessed weighted-A* and RRT, RRT* algorithms for the robot's goal-reaching performance
 - RRT achieved 30 % faster and more memory-efficient performance, while A* showed superior path quality with shorter path
 - Provided insights into expanded nodes, sampling method heuristic selection (Euclidean, Manhattan distance), aiding algorithm selection based on complexity, efficiency trade-offs, and graph creation efficiency in the sampling-based approach

INTERNSHIP EXPERIENCE

- **ABB Robotics** Bengaluru, India
Intern May 2017 - July 2017
 - Developed a [robotic system](#) where an anthropomorphic robotic arm was attached to a 6-DOF IRB1600 ID ABB Industrial Robot to explore grasping.
 - Was involved in the mechanical design, programming and basic electronic design of the system.
- **NMCAD Lab, Aerospace Department, Indian Institute of Science** Bengaluru, India
IASc-INSa-NASI Joint Academies' Research Fellow (Summer Research Fellowship) May 2016 - July 2016
 - Worked on Design of Flapping-wing type Micro Aerial Vehicles using self-actuated composites
 - The design was based on the flapping pattern of the rufous hummingbird (*Selasphorus rufus*) with the mechanism to allow 2 degrees of freedom for figure 8 like configuration

TEACHING EXPERIENCE

- **MAE3: Introduction to Mechanical Design** University of California, San Diego
Graduate Teaching Assistant Oct 2022 - Dec 2022
 - Designed bearing devices to demonstrate basic concepts of under-constraint, exact constraint and over-constraint bearing designs to students
 - Conducted physics review for MAE3 students
 - Conducted weekly office hours at the Design Studio

ACTIVITIES

- **Volunteer at Youth for Seva**
A not-for-profit NGO in India supporting schools and other organisations in social sector
- **Amateur Runner and Cyclist**
A weekend activity to explore new places and test personal limits
- **Former Secretary of Association for Computer Machinery, Student Chapter, NITK**
Managed club activities such as the project expo

REFERENCES

- **Dr. Jagannath Raju** CTO, Systemantics India Pvt. Ltd
jagannath@systemantics.com. PhD, MIT
- **Prof. Michael Yip** Associate Professor, UCSD
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- **Prof. Nikolay Atanasov** Assistant Professor, UCSD
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