

# MARK JENNINGS

www.makr.org  
markjennings97@gmail.com  
254.760.5530

Work Experience	Skills
<p><b>Nuclear &amp; Applied Robotics Group</b> <i>Graduate Researcher   2019 – 2021</i></p> <ul style="list-style-type: none"><li>• Developed intuitive controller for novel passively-balanced manipulator</li><li>• Refactored codebase for custom robot arm to leverage open-source libraries and increase modularity</li></ul>	<p><b>Experienced:</b></p> <ul style="list-style-type: none"><li>• C++</li><li>• CAD (SolidWorks)</li><li>• Robot Operating System (ROS)</li><li>• MATLAB</li><li>• Additive Manufacturing</li><li>• Machining, CNC</li></ul>
<p><b>Sandia National Labs</b> <i>R&amp;D Intern   Summer 2019</i></p> <ul style="list-style-type: none"><li>• Designed and qualified additively-manufactured metal components</li><li>• Received 1<sup>st</sup> place intern presentation</li></ul>	<p><b>Familiar:</b></p> <ul style="list-style-type: none"><li>• Python</li><li>• Simulink, LabVIEW</li><li>• HTML, CSS, JavaScript</li></ul>
<p><b>Appttronik Systems</b> <i>Engineering Intern   Summer 2018</i></p> <ul style="list-style-type: none"><li>• Derived forward kinematic equations for 10DoF humanoid bipedal robot</li><li>• Updated actuator testbed product to achieve higher payloads with lower fabrication costs</li></ul>	Education
<p><b>ReNeu Robotics Lab</b> <i>Undergraduate Researcher   2016 - 2019</i></p> <ul style="list-style-type: none"><li>• Designed and fabricated components for rehabilitation robots</li><li>• 3D-printed and assembled custom hand and finger prosthetics</li></ul>	<p><b>MS Mechanical Engineering</b> <i>UT Austin   2019 – 2021   3.96 GPA</i></p> <ul style="list-style-type: none"><li>• Funded by Department of Energy</li></ul> <p><b>BS Mechanical Engineering</b> <i>UT Austin   2015 – 2019   3.84 GPA</i></p> <p><b>Coursework topics:</b></p> <ul style="list-style-type: none"><li>• Autonomous Robots</li><li>• Manipulator Algorithms</li><li>• Classical &amp; Modern Control</li><li>• Robot Mechanism Design</li></ul>