

MARK JENNINGS

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