

Ella Majkic

UBC Engineering Physics

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EDUCATION

Engineering Physics, The University of British Columbia

Sep 2023 - Present

Minor in Honours Mathematics

Awards: Trek Excellence Scholarship; Eric P. Newell Engineering Award; Dean's Scholar

GPA: 90%

SKILL SUMMARY

Software: C, C++, Python, Git, Linux, ROS, OpenCV, TensorFlow, MATLAB/Simulink, Java, JavaScript

Tools: KiCad, OnShape, LaTeX, CMake, Bash/Linux Shell, COMSOL Multiphysics, GDB, FPGA/VHDL

EXPERIENCE

TRIUMF Particle Accelerator

Jan 2025 - May 2025

Research Engineer Co-op, PIONEER Experiment

- Developed and tested Purity Monitor Assembly (PUMA) calibration for rare pion decay experiment
- Simulated electron drift using COMSOL and C++, validating models against experimental data
- Designed and built a vacuum system for PUMA calibration tests, achieving stable 1e-6 bar
- Led first successful PUMA calibration tests, performing statistical analysis in Python and MATLAB
- Implemented RS-232-based data acquisition for vacuum gauges and detector readout in LabVIEW

UBC Open Robotics

Sep 2023 - Mar 2025

Software Engineer, Navigation Subteam

- Developed autonomous navigation for service robot competing at international RoboCup@Home
- Used Python to implement ROS-based navigation algorithms and SLAM in dynamic environments

PROJECTS

[\[Portfolio\]](#)

Simulated Detective Agent

Deep Learning, TensorFlow, ROS, Computer Vision, CNN, Linux

- Trained and integrated multiple robust machine learning models from scratch to enable a ROS robot agent to autonomously solve a detective-style task in Gazebo simulation
- Designed and trained a convolutional neural network on a custom, augmented 1,000+ image dataset, achieving 99.1% validation accuracy on alphanumeric character recognition
- Used YOLOv8 and OpenCV for dynamic clue board and NPC detection in environment
- Applied imitation learning to train a neural policy achieving perfect driving through course

Autonomous Pet Rescue Robot

C++, Electronics Design, Rapid Prototyping, PCB Assembly

- Developed, prototyped, and built a fully autonomous robot with a team capable of line following through a multi-terrain course while identifying and retrieving pet stuffies
- Designed and soldered electrical systems for motor control, microcontroller integration, and sensing
- Wrote C++ libraries to interface with 2D LiDAR, H-bridges, phototransistor sensors, and dynamic claw, enabling the robot to perceive and interact with its environment

Motor Control Feedback Circuit

Digital Logic, Electronic Hardware, Circuit Design, Counters, Latches

- Built a fully hardware-implemented PID controller for active motor speed control
- Processed phototransistor speed outputs using Schmitt triggers, DACs, op-amps, and digital logic