# Junhyeok **Ahn**

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## Education

**University of Texas at Austin** — *Austin, Texas, U.S.A*

Ph.D. Student — *Aug. 2016 - Present*

- GPA:3.95/4.0

**Hanyang University** — *Seoul, S.Korea*

B.S. in Mechanical Engineering — *Mar. 2010 - Feb. 2016*

- GPA:3.75/4.0

## Work Experience

**Human Centered Robotics Lab in UT Austin** — *Austin, Texas, U.S.A*

Graduate Research Assistant — *Sep. 2017 - PRESENT*

- Draco Project
- United States Special Operations Comman Exoskeleton Project

**Apptronik Inc.** — *Austin, Texas, U.S.A*

Control & Software Engineer — *Jun. 2017 - Aug. 2017*

- Developed high performance poisition and force controller in embedded system and multi degree of freedoms control architectures in Unix system for newly invented Viscoelastic Liquid Cooled Actuator.

**Dep. of Management Information System** — *Austin, Texas, U.S.A*

Teaching Assistant — *Jan. 2017 - May. 2017*

- Assisted teaching materials on Data Mining (MIS 373).

**Firmware Bank** — *Seoul, S.Korea*

Internship — *Jan. 2015 - Jul. 2015*

- Processed sensor signals for remote controlled cars and quad-copters.

## Skills

**Programming** C/C++, Python, Matlab, Vim

**Languages** Korean, English

## Publications

### Journal Articles

Investigations of a Robotic Testbed with Viscoelastic Liquid Cooled Actuators
Donghyun Kim, Junhyeok Ahn, Orion Campbell, Nicholas Paine, Luis Sentis
*CoRR* abs/1711.01649 (2017). 2017

### Conference Proceedings

Computationally-Robust and Efficient Prioritized Whole-Body Controller with Contact Constraints
Donghyun Kim, Jaemin Lee, Junhyeok Ahn, Orion Campbell, Hochul Hwang, Luis Sentis
*arXiv preprint arXiv:1807.01222* (2018). 2018

Investigations of viscoelastic liquid cooled actuators applied for dynamic motion control of legged systems
D. Kim, O. Campbell, J. Ahn, L. Sentis, N. Paine
*2017 IEEE-RAS 17th International Conference on Humanoid Robotics (Humanoids)*, 2017

## Presentation

**Dynamic Walking Conference** — *Stockholm, Sweden*

Presenter for research — *June. 2017*

- Talked about kinodynamic planning for humanoid robot.