My prior research has investigated how the material properties and dynamics of origami-inspired, foldable robots can be taken advantage of without increasing the complexity or costs. For the first project that I worked on when I joined Dr. Aukes’ lab, we developed a methodology to leverage the deficiencies of soft, low-cost, informal systems to our advantage to sense contacts in a way that rigid systems cannot. I individually designed a device with built-in force sensing and coded a force-feedback controller for it. My current work focuses on understanding the unique considerations of laminate robots that need to be accounted for to use informal simulators to develop a high-performance jumping robot. I am individually responsible for designing the legs for this robot and have programmed dynamics simulations to optimize their design. I found that a purely theoretical approach is insufficient and am currently fitting unknown simulation parameters to empirical results.