Max Freeman

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Education

University of California, Berkeley **May 2025**
Master of Engineering in Mechanical Engineering, *Concentration in Controls & Robotics* GPA: 3.98

Cornell University **May 2024**
Bachelor of Science in Mechanical Engineering GPA: 3.77 | *Magna Cum Laude*

Skills

Robotics: ROS2 | Feedback Control | State Estimation | Embedded Systems | Model Predictive Control | CAN Bus
Hardware: Mechatronics | System Integration | Mechanical Design | Prototyping & 3D Printing | Root Cause Analysis
Programming Languages: Python | C++ | MATLAB
Software & Tools: SolidWorks | Fusion 360 | GitHub | Simulink | Asana | Pyomo
Leadership: Project Management | Cross-Functional Collaboration | Stakeholder Engagement | Agile Development

Highlighted Experience & Projects

Lead Robotics Engineer, *Multimodal Autonomous Robot Design (MEng Capstone)* **September 2024 - Present**

- Lead a team of 4 engineers in a full-stack robotics development project, integrating mechanical design, embedded electronics, and real-time software to build a multimodal robot capable of both driving and flying.
- Design and deploy a custom ROS2-based flight controller for aerial mode, integrating motion capture feedback and validating stable hover and recovery behavior across 10+ tethered flight tests.
- Develop and tune real-time MPC algorithms in Python for trajectory tracking and obstacle avoidance, achieving under 5 cm lateral error in final position during hardware testing.
- Deploy ROS2 nodes on an NVIDIA Jetson to interface with a motion capture system and control four actuators via CAN Bus, enabling synchronized execution across perception and actuation layers.
- Conduct software- and hardware-in-the-loop testing to validate system reliability, identify failure points early, and implement safety-critical failsafes that mitigate risks and enable repeatable flight experiments.

Control of Autonomous Flight Project, *University of California, Berkeley* **September 2024 - December 2024**

- Developed a quadcopter flight controller in C++, achieving precise attitude, altitude, and position control.
- Implemented sensor fusion models in C++, utilizing data from optical flow, IMU, and Time-of-Flight sensors to improve sensor data accuracy and provide precise feedback for control.
- Diagnosed and resolved stability issues through targeted subsystem testing, sensor debugging, and controller tuning to validate fixes and improve system response.

Mechanical Design Intern, *Lit Motors* **June 2024 - July 2024**

- Collaborated with cross-functional teams in a fast-paced startup to develop a novel two-wheeled EV.
- Designed a custom dual-plane dynamic balancing rig for Control Moment Gyroscopes using SolidWorks, providing a crucial testing platform to reduce vibrations and improve the operational stability of the CMG.
- Iterated on designs for the vehicle steering system and CMG base-ring in SolidWorks, improving chassis integration and reducing manufacturing complexity.

Fast Robots Project, *Cornell University* **January 2024 - May 2024**

- Owned end-to-end development of an embedded autonomous RC robot, integrating IMUs, sensors, and motor drivers on an Arduino Nano and implementing real-time control logic in C++ and Python.
- Integrated Time-of-Flight and IMU sensors using I2C, applying sensor fusion techniques and software-based filters in C++ to minimize sensor output noise by over 50%, enhancing system performance and reliability.
- Implemented and tuned distance-based PID controllers, reducing settling time by 40%.
- Diagnosed hardware issues with an oscilloscope and resolved control and sensing faults by analyzing telemetry and sensor data, improving reliability and reducing latency.

Rapid Prototyping Intern, *Kullman Lab, UCL* **July 2023 - August 2023**

- Designed and iterated on custom 3D-printed mounts for a biomedical automation system, optimizing for volumetric constraints while enhancing modularity, ease of access, and user functionality.
- Conducted rapid iterative prototyping using 3D printing, refining designs based on continuous user feedback to enhance functionality and ease of use.