

Jorge Ortega Camazón

Boston, MA | ortega.jor@northeastern.edu | (617) 963-4144 | www.linkedin.com/in/jorge-ortega-camazon

EDUCATION:

Northeastern University, Boston, MA **May 2026**

Master of Science in Robotics, Concentration: Electrical and Computer Engineering **GPA: 4.0**

Relevant Courses: Robotics Sensing and Navigation, Reinforcement Learning, Robot Mechanics and Control

Universidad de León, León, Spain **Jul 2024**

Bachelor of Science in Industrial Electronic and Automation Engineering

Relevant Courses: Robotic Prototypes, Automatic Control, Power Electronics, Digital Electronics

*Studied abroad during the academic years 2018-2019 and 2022-2023 in USA and Italy respectively

TECHNICAL SKILLS:

Software: LTspice, MATLAB, EAGLE, Fusion 360, SolidWorks, AutoCAD, ROS, Gazebo, RViz, MS Office Tools

Hardware: Soldering, PCB design, Arduino, ESP32, Analog circuits, Electronic equipment

Programming Languages: Python, C++, MATLAB

Robotics and Automation: SLAM, LiDAR, IMU, GPS

Languages: Spanish (Native), English (Fluent), Italian (Conversational)

PROJECTS & EXPERIENCE:

Graduate Researcher

May 2025 – Present

Silicon Synapse Lab, Northeastern University

- Implemented multi-language (Python/C**/MATLAB) workflows using Pinocchio library to import biped robot URDFs, compute inverse/forward dynamics and kinematics, and visualize inertial properties in Drake

Stable Walking on Biped Robot using RL

Feb – Apr 2025

- Trained a customized biped robot in the MuJoCo Walker2D-v5 environment using a PPO algorithm based on the Stable Baselines3 library, achieving stable and consistent forward locomotion
- Developed tailored Python code enabling parallel training across 4 environments, integrating TensorBoard for real-time performance tracking and facilitating hyperparameter tuning
- Modified reward functions, torque limits and agent's geometry to encourage realistic motion dynamics, enabling energy-efficient walking and high-speed running behavior across tests

Synchronization and Coordination of Mobile Robots

Nov – Dec 2024

- Simulated a multi agent robot system for autonomous exploration within a shared environment based on the open-source *TurtleBot 3* robot ROS packages
- Modified autonomous navigation algorithms and configured SLAM launch files for 3 individual robots to enable simultaneous multi-agent exploration in customized Gazebo environment using ROS Noetic
- Configured Rviz for real-time visualization of each robot's exploration process and dynamically merged maps to generate a complete representation of the environment

Control System Optimization for a Two-Elevator Building

Nov – Dec 2024

- Developed and simulated an optimized elevator control system in MATLAB to improve time and energy efficiency in a multiple-elevator building
- Designed and implemented three different elevator controllers for later analysis of system performance
- Utilized parallel computing techniques to enable real-time multi-elevator operation and dynamic request allocation, obtaining realistic request handling and decision-making
- Evaluated control system performances by assessing efficiency metrics such as total travel time, floors traversed and workload balance, achieving a 250% improvement in time and optimal workload balance

Low-Cost, Multifunctional Autonomous Robot

Feb – Jul 2024

- Engineered an autonomous robot for indoor mapping with a focus on cost-efficiency using durable, lightweight materials, optimizing weight distribution for stable operation in diverse environments
- Integrated an RPLiDAR A1M8 for real-time mapping and a GPS NEO-M8N for localization, enabling precise navigation with ESP32 microcontrollers
- Developed custom firmware to process and filter data, manage communication between microcontrollers and sensors, and implement motor control and navigation logic.
- Achieved a functional prototype capable of autonomous navigation and mapping with a cost inferior to \$300, demonstrating a potential affordable alternative to commercial Autonomous Mobile Robots