




Nathan Rogers

603-400-7544 — Portfolio  — LinkedIn: nathanrogers22433b199  — GitHub: torn8to 

Professional Summary

Junior Robotics Engineer seeking to leverage hands-on experience in Sensor Processing, Mapping, Navigation. Building robust navigation and mapping systems for autonomous robots. Incorporating deep vision models and training them for efficient inference on edge devices.

Experience

Robotics Engineering Intern

West Warwick, RI

Smartapp

2021-2022

- Developed and tested a handheld sensor platform for the development of algorithms for mobile robotics applications.
- Combined opensource sfm pipelines with 3d structural data to model and measure and provide insight using BIM information.

Consulting Embedded Engineer

Remote

Freelance/Part-Time Role

2020 - 2021

- Designed Electronics hardware and programmed stm32h7 chips an absolute force sensor matrix.
- Built web ui for sensor data visualization and analysis speeding up data analysis and reducing experiment time by 87% over existing methods.
- Built a Camera integrated with an edge ai processor deployed with a distilled performant image segmentation for manufacturing quality control.

Education

Bachelor of Science in Robotics Engineering

Worcester, MA

Worcester Polytechnic Institute





2019-2023

Relevant Coursework: Robotics Manipulation, Robotics Design, Digital Electronics, Computer Vision, Machine Learning, Software Engineering

Skills

- **Programming Languages:** C/C++, Python, SQL, Cuda
- **Robotics Technologies:** ROS/ROS2, Gazebo, Docker, KiCad
- **Machine Learning:** Pytorch, Weights and Biases,
- **Electronics:** I2C, CAN, SPI, UART,

Projects

- **Sensor Agnostic Lidar SLAM** : Developed a sensor agnostic lidar with optional odometry with an efficient and robust cpu based icp registration achieving an average of 40fps and a backend loop closure detection using birds eye view image matching and pose graph optimization for improved global positional accuracy.
- **Imu Estimation Kalman Filter** : Developed an imu Extended Kalman Filter for sensor fusion of imu and odometry data. To determine accelerometer and gyroscope bias. To determine bias of an imu in conditions when lacking a warmup period for efficient imu integration.
- **Quadruped Learning to Walk** : Teaching a Quadruped robot to walk using reinforcement learning through Proximal Policy Optimization. Utilizing real2sim techniques to bridge the gap between simulation and real world.
- **Cuda Iterative closest Point Registration** : Robust scan to map icp registration algorithm using cuda gpu for efficient registration of improving registration speed up by 3.75x on average compared to 16 core cpu.