

GAN TU (MICHAEL)

Pasadena, CA • tugan@berkeley.edu • +1 (626) 628-4911 • GitHub: Michael-Tu • LinkedIn: gantu • Web: tugan.me

EDUCATION	University of California, Berkeley B.A. Computer Science GPA: 3.925/4.0	2015 - 2019
	<ul style="list-style-type: none">• 1 of 49 current honors students in the undergraduate computer science department• Relevant Courses: Artificial Intelligence, Machine Learning, Deep Learning, Natural Language Processing, Data Structures, Machine Structures, Algorithms, Linear Algebra, Discrete Math, Multivariable Calculus, Statistics, Probability Theory, Signals & Circuits, Database, UI/UX ResearchUdacity Nanodegree Programs: Self Driving Car, Robotics, Digital Marketing, Deep Learning, VRCoursera: 5 classes in full stack web development, 28 Wharton specialization classes in business	
TECHNICAL HIGHLIGHT	<p>Proficient: Python, Java, Deep Learning, NLP, SQL, NoSQL, Tensorflow, Keras, PyTorch, AWS, Git, UNIX, Full Stack Web Development (HTML, CSS, Flask, Bootstrap), NumPy, Matplotlib, Pandas, NLTK, UI/UX</p> <p>Familiar: Bash, C, C++, JavaScript (including jQuery, Ajax, Angular.js), MIPS, LISP, Apache Spark, Swift</p>	
EXPERIENCE	Full Stack Web Developer	June 2016 - Present
	<ul style="list-style-type: none">• Designed & deployed 6+ responsive web apps (Flask, Angular.js) full-stack for various client needs.• Reengineered NASA Starlight program's legacy aerospace photon propulsion online modeling tool with a new file system, front-end interface, and more sophisticated modeling functionalities.	
	DL Researcher & External Officer <i>Machine Learning at Berkeley</i>	Sept. 2016 - Present
	<ul style="list-style-type: none">• Researched lightweight, real-time object detection architectures that reduce the network size of FCN-based SqueezeDet by 12.5% with only 2% loss in mAVP using partial-layer weight quantization.• Lead club external relations, graphic design, and marketing efforts. Worked on machine learning tutorials, which were all ranked top 3 on HackerNews and ranked #1 on Reddit ML sub-reddit.• Wrote and deployed stock scrapers in AWS to crawl 1M+ S&P 500 minute-by-minute trading data from stock charts and store them in NoSQL and SQL database, later used to train trading predictors.	
PROJECTS	Autonomous Vehicle -- Software <i>Computer Vision & Deep Learning</i>	May 2017 - Present
	<ul style="list-style-type: none">• Experimented and trained various neural network models (end-to-end, CNN, FCN) that classify traffic signs at 94% mAVP, perform generalizable behavioral cloning on human driving behaviors, and conduct image segmentation of human figures, based directly from front-camera image stream.• Integrated traditional image analysis techniques using OpenCV. Developed high-accuracy pipelines to identify lane lines and curvature, and to detect and track vehicles under varied lightings.• Program Kalman filters and particle filters using sensor fusion and Markov localization to precisely determine the location of other vehicles on a map at single-digit centimeter-level accuracy.• Build both PID controllers and model predictive controllers for advanced vehicle actuation.• Construct finite state machines for path planning using data and model driven behavior predictions.• Learn more from my comprehensive write-ups and video demos at code.tugan.me/self-driving-car.	
	Machine Linguists <i>Natural Language Processing</i>	April 2017 - Present
	<ul style="list-style-type: none">• Engineered and trained a MEMM-based POS tagger (95.7% mAVP), a transition-based dependency parser (67% mAVP), and a pronominal coreference resolution parser (77%+ mAVP) with custom engineered features and self-implemented Markov models, and decoding & parsing algorithms.• Engineered and trained both LSTM-RNN-based and seq2seq-based neural network models for English-French machine translation and Simpsons television scripts, language generation tasks.	
	Intelligent Bots <i>Robotics</i>	May 2017 - Present
	<ul style="list-style-type: none">• Designed and implemented ROS-based prototypes that manipulate simulated robotic arms with six degrees of freedom for collision avoiding object localization, relocation, and motion planning.• Built autonomous rover models for high fidelity environment mapping and rock sample extraction.	