

Jesse Miller

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EXPERIENCE

Motional

Boston, MA

Principal Robotics Control Engineer

May 2024 – Present

- Designed, trained, and deployed a **PPO-based RL Planner** using PyTorch which outperformed the company's imitation learning based ML planner in comfort and safety in most scenarios in sim and on-vehicle.
- Led a cross-org Reflexive Planner project**, a low latency task for collision prevention critical to achieving the Driverless milestone. Coded features that **reduced false-positive rate by 400%** and designed regression tests and metrics for performance monitoring. Presented results directly to **Motional's CTO**.
- Awarded Motional's monthly "**Mobilizer Award**" and consistently received "exceeds expectation" for every performance review.

Senior Robotics Control Engineer and Team Lead

August 2020 – May 2024

- Code-owner and developer for a **nonlinear trajectory optimization** formulated with FORCES Pro in Python and deployed in C++.
 - Collaborated to implement and **patent a novel Contingency MPC** approach for handling multi-modal predictions in trajectory optimizer.
 - Invented a novel algorithm for generating assertive lane change trajectories across planning control stack; deployed on AV.
 - Tuned controller performance on-vehicle, contributing to investor analysts' feedback that ride was "**smoother than Waymo's**".
- Led Path Tracker Performance team (6 ppl) creating Python and SQL metric frameworks, automating release tests, and improving LQR tracking performance. Reduced rate of high cross-track error from **25 to 1 violation per 1K miles**.
- Collaborated with team to formulate and implement a **convex trajectory optimizer** using OSQP, reducing latency by 50%.
- Developed MySQL metric dashboards for visualization, triage, and drilldown of controls related errors; monitored weekly.
- Led Trajectory Formulation Team** for a quarter; defined team's north star strategy, conducted one-on-ones, and oversaw successful demo deployment.
- Developed and patented an **ML based vehicle dynamics model** for simulation (LSTM in PyTorch) and deployed it in C++, reducing avg displacement error by 40% compared to physics based model.
- Primary code owner and developer for repo containing Python analysis scripts used for AV log visualization and debug, regularly used by 30+ people.

Robotics Control Engineer III

October 2018 – August 2020

- Owner of a dynamic bicycle model based **path tracker module**, refactoring and integrating code during company merger.
- Designed and coded 'Mock Planner' & 'Fault Injection' tools in C++ and Python used to stress test controller & for vehicle operator training.
- Curated a set of ride comfort metrics (e.g. motion sickness likelihood), implementing extractors to monitor comfort trends.
- Mentored intern who explored trajectory optimizer solver modifications for improved latency and performance.

Autonomous Vehicle Engineer

August 2017 – October 2018

- Worked on vehicle integration and sensor calibration, outfitting the Renault Zoe EVs with nuTonomy's AV compute stack.
- Streamlined AV closed course testing, curating a weekly KPI report on AV performance shared with C-Suite.

Sandia National Labs

Albuquerque, NM

R&D Electromechanical Engineer and Technical Lead

August 2016 – August 2017

- Tuned a PID controller for a DC motor system using system identification and control design methods in MATLAB/Simulink.
- Developed a tester using fiber optics, PXI, LabView, 3D printing, and control design to quantify a mechanism's performance.
- Designed tests and analyzed results to characterize the performance of various mechanisms relating to nuclear weapon safety.
- Modeled 3D multibody rigid body dynamic mechanism using Siemens LMS software and performed tests to verify the model.

Autonomous Sailboat Project

Ithaca, NY

Master's Thesis, Dynamics Subteam Lead

January 2015 – May 2016

- Created a [simulation framework](#) to model the 3D dynamics of a sailboat in MATLAB to determine the feasibility of autonomously sailing around the world.
- Wrote a [thesis paper](#) describing a novel ‘rudder connected to sail’ design to improve the directional stability of a robotic sailboat.
- Presented findings at a [robotics seminar](#) with advisor [Andy Ruina](#) at Cornell University and received the [Kelly Prize](#) for aerospace related research.
- Provided recommended robotic sailboat design to [CUSail project team](#) at Cornell which they built and tested on Cayuga Lake, verifying the simulation results.

Engineering Dynamics Class (MAE 2030)

Ithaca, NY

Graduate Teaching Specialist

January 2016 – May 2016

- Taught two recitation sections with about 15 students in each, held regular office hours, and graded exams.
- Volunteered to fill in for the Professor, teaching a one-and-a-half-hour lecture to about 150 students.
- Received **4.88/5 overall rating** on my TA evaluation based on 16 student responses and was nominated to be a TA trainer.

Amazon Robotics

North Reading, MA

Data Analyst and Performance Intern

May 2015 – August 2015

- Created a random forest machine learning predictor using Python and MySQL to predict the time it takes to pick an item off a shelf.
- Designed a Linux service using Java and XML, allowing the predictor to be easily used.
- Implemented the predictor service with a performance website, improving metrics used to assess employee performance.

Innovative Scientific Solutions Inc.

Dayton, OH

Engineering Co-op Student

January 2014 – August 2014

- **Invented** a unique idea to listen to the sounds produced by handwriting and understand what was written.
- Developed and [coded a MATLAB program](#) to transcribe handwriting by only using a microphone.
- [Presented my invention](#) in a **U.S. Air Force wide competition** against 37 other inventions.
- **Won** the competition and received \$15,000 in research funding and a patent for the invention.
- Designed in NX Unigraphics and performed an experiment to test the effects of unsteady flow through an intercooler.
- Published and presented a [conference paper](#) based on these findings in the SAE 2014 Aerospace Conference.

Autonomous Systems Laboratory

Ithaca, NY

Mechanical Engineering Researcher

August 2014 – December 2014

- Developed and wrote Python handlers to control a robotic ball, Sphero, with a path planning program, LTLMoP.
- Successfully demoed the code, having Sphero autonomously traverse a map and react to its environment.

EDUCATION

Cornell University, College of Engineering | Ithaca, NY

August 2015 – May 2016

Master of Engineering Robotics, Controls, and Dynamics

GPA: 4.17/4.0

- [Outstanding Achievement Award](#): Given to top two MechE Masters students with the **highest academic standing**.
- [Kelly Prize](#): Excellence in aerospace engineering, received for research on a novel robotic sailboat design.
- **Relevant Courses**: Autonomous Mobile Robots, Robot Motion, Feedback Control, Multivariable Control Theory, Advanced Dynamics.

Cornell University, College of Engineering | Ithaca, NY

August 2011 – May 2015

Bachelor of Science in Mechanical Engineering

Major GPA 4.24/4.0 | Cumulative GPA: 4.15/4.0

- [Sibley Prize](#): Awarded to the two mechanical engineering graduating seniors with the **highest overall GPA**.
- [Frank O. Ellenwood Prize](#): Awarded to the M.E. students with the **highest GPA** in heat and power courses.

SELECT PATENTS

- **Autonomous Driving Mode Engagement**, [US patent US20230159063A1](#), March 25, 2023. I developed a method for comfortable and safe transition from manual to autonomous vehicle control.
- **Control Architectures for Autonomous Vehicles**, [US patent US11794775B2](#), October 24, 2023. I collaborated to develop and implement novel trajectory optimization based control methods.
- **ML Based Vehicle Dynamic Simulator Model** (patent pending), Docket No. I2023099, May 24, 2023. I helped design and deploy an LSTM model trained on vehicle dynamics.
- **Shortened Contingency Horizon MPC With a Terminal Car-Follow Constraint** (patent pending), Docket No. I2023017, January 27, 2023. I designed and implemented a sparse contingency trajectory optimization formulation that improved solve-time while maintaining recursive safety guarantees.
- **Autonomous Vehicle with Contingency Consideration in Trajectory Realization** (patent pending), Application No US18164652, February 6, 2023. I co-designed and implemented a joint trajectory optimization formulation for safely and comfortably handling multimodal predictions.

SKILLS & INTERESTS

Languages: Python, C++, MATLAB, SQL, LabVIEW, C

Technologies: PyTorch, FORCES Pro, Stable-Baselines3, OSQP, Ubuntu/Linux, Git, CMake, Bazel, L^AT_EX, Jupyter notebook, Simulink, OpenCV, Raspberry Pi, Arduino, SolidWorks, Blender

Continued Education: [Deep Reinforcement Learning CS285](#), [Underactuated Robotics MIT 6.832](#), Udemy Design Patterns in C++

Interests: Acoustic guitar, ping pong, badminton, tennis

PROJECTS

Gamified Vehicle Path Tracking | [GitHub](#)

- I implemented a variety of tunable path tracking algorithms (e.g. LQR, Stanley, Pure Pursuit) in Python, wrapped in a gamified dynamic vehicle simulator. The user draws a b-spline path guiding the vehicle through a series of obstacles. The user can interactively tune the controllers and view Jupyter notebooks with derivations of the algorithms.

Balancing Robot | [GitHub](#)

- A balancing cart-pole type robot, using cascaded PID control and complementary filter for state estimation. I designed and built the hardware and electronics and wrote the software.

Additional Projects: [Autonomous Sailboat 3D Dynamics Simulator](#) (MATLAB), [Color Following Robot with Articulated Camera](#) (Python, OpenCV), [Aesthetically Rendered Double Pendulum Simulation](#) (Blender/Python API), [WriteHear: Transcribe handwriting from sound](#) (MATLAB), [Bouncing Ball Simulation](#) (C++), [2D Geometric Shooter Game](#) (Python)