

# XUXIN CHENG

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## EDUCATION / AWARDS

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**University of California, Berkeley**, Berkeley, CA

07/2019 – Present

Visiting student, EECS; GPA: 3.94/4.0

- Selected Courses (All grad level): CS285 Deep Reinforcement Learning; CS194 Computer Vision; EECS206 Introduction to Robotics; EE127 Optimization Models; ME193 Legged Robots; ME 299 Individual Research

**Beijing Institute of Technology**, Beijing, China

09/2016 – 07/2020

B.S. in Automation Engineering; GPA: 91.5/100 (Rank 1/167)

- National Scholarship (0.2%); DWIN Scholarship (1%); Outstanding Student Scholarship (5%, 5 times)
- Graduation with honor: Outstanding Graduate of Beijing & BIT

## PUBLICATIONS

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- **Xuxin Cheng**, Zhongyu Li, Xue Bin Peng, Pieter Abbeel, Sergey Levine, Glen Berseth, Koushil Sreenath. “Learning Precise Foot Placement Skills for Bipedal Robots”. In preparation for *IEEE Robotics and Automation Letters (RA-L)*
- Zhongyu Li, **Xuxin Cheng**, Xue Bin Peng, Pieter Abbeel, Sergey Levine, Glen Berseth, Koushil Sreenath. “Reinforcement Learning for Robust Parameterized Locomotion Control of Bipedal Robots”. Submitted to *IEEE International Conference on Robotics and Automation (ICRA)* 2021
- Fei Ye\*, **Xuxin Cheng\***, Pin Wang, Ching-Yao Chan. “Automated Lane Change Strategy using Proximal Policy Optimization-based Deep Reinforcement Learning”. *IEEE Intelligent Vehicles Symposium (IV)* 2020
- Tianyu Shi, Pin Wang, **Xuxin Cheng**, Ching-Yao Chan. “Driving Decision and Control for Automated Lane Change based on Deep Reinforcement Learning”. *IEEE International Conference on Intelligent Transportation (ITSC)* 2019

### Posters

- Pin Wang, Fei Ye, **Xuxin Cheng**, Ching-Yao Chan. “Lane Change Strategy based on Meta Reinforcement Learning”. *Berkeley Artificial Intelligence Research Annual Workshop* (2019)

\* denotes equal contribution

## EXPERIENCE

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**Hybrid Robotics Lab (HRL)**, UC Berkeley

01/2020 - Present

Advisor: Koushil Sreenath & Sergey Levine

Berkeley, CA

- Propose and implement the reinforcement learning-based controller for precise foot placement skills of bipedal robot Cassie, with foot placement information extracted from an on-board RGB camera.
- Propose and implement the approach for training bipedal robot in simulation to perform diverse and robust locomotion skills; Successfully transfer learned policy to the real robot.

**Partners for Advanced Transportation Technology (PATH)**, UC Berkeley

7/2019 - 02/2020

Advisor: Ching-Yao Chan

Berkeley, CA

- Propose the framework for optimizing lane change maneuver in highway environment with Deep Reinforcement learning. Proposed method performs favorably against baseline approaches.

**PKU Omni Smart Sensing Lab (POSS)**, Peking University

07/2018 - 12/2018

Advisor: Huijing Zhao

Beijing, China

- Process data from RGB and Lidar inputs of autonomous vehicles in field environments. Implement traversable area segmentation using inverse reinforcement learning.

## SERVICES

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Peer reviewer for *IEEE Intelligent Vehicles Symposium (IV)* 2020

## SKILLS

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**Languages:** Python, C++, JavaScript, HTML, Assembly Language

**Softwares&Tools:** MATLAB, ROS, Tensorflow, Pytorch, MuJoCo, PyBullet, Git, L<sup>A</sup>T<sub>E</sub>X