

ALFRED CUEVA

☎ (470)338-2676

🌐 alfred-cueva.github.io

✉ alfred.cueva@gatech.edu

🌐 [Linkedin](#)

🐙 [GitHub](#)

EDUCATION

Georgia Institute of Technology

MS in Robotics

Aug. 2025 – May 2027

Georgia, United States

- Coursework: Deep Reinforcement Learning, Computer Vision, Optimal Control

Seoul National University

BS in Mechanical Engineering (Robotics Concentration) | GPA: 9.12/10.0

Mar. 2020 – Feb. 2024

Seoul, South Korea

- Coursework: Reinforcement Learning, Humanoid Robotics, Autonomous Navigation, Deep Learning, Linear Control

SKILLS

Languages: Python, C++, MATLAB, Julia

Frameworks: Pytorch, ROS, Git, Gazebo, Isaac Gym/Sim/Lab, PyBullet, MoveIt, MuJoCo, CoppeliaSim

Key Competencies: Reinforcement Learning, Motion Planning, Root Cause Analysis

WORK EXPERIENCE

Samsung

Robotics Engineer

Mar. 2024 – Aug. 2025

Seoul, South Korea

- Developed obstacle detection system using YOLOv5 for collaborative robots with 92% accuracy.
- Engineered control software using Disturbance Observer, reducing steady-state error by 15% and enhancing precision of a novel 7-DOF manipulator. This work was awarded \$10,000 in the [\[Smart Construction Challenge\]](#).
- Implemented RRT* for KUKA/DOOSAN mobile manipulators, enabling their operation in cluttered environments.
- Engineered Hybrid A* for collaborative robots, creating ROS pipelines and testing environments towards integration.
- Designed human-machine interface for robotic operation, integrating software with visualization tools (Rviz, Gazebo).

Samsung

Engineering Intern

Jul. 2023 – Aug. 2023

Seoul, South Korea

- Engineered heat anomaly detection models for semiconductor sites, improving heat map estimation efficiency by 40%.
- Developed Python scripts with PixyCam for real-time human orientation tracking relative to AGVs, enabling safety-aware navigation and object avoidance in lithography rooms.

RESEARCH EXPERIENCE

Georgia Institute of Technology | LIDAR Lab | Prof. Ye Zhao

Aug. 2025 – Present

- Developing policies for humanoid robots to perform complex loco-manipulation tasks, such as opening doors and transporting boxes, using diffusion policy fine-tuning with reinforcement learning in the loop. *Under review for RA-L.*
- Investigating generative diffusion planning methods integrated with non-differentiable optimization modules to enable safe and efficient robot motion under constraints, such as manipulation in the Avoiding Environment from D3IL.

Seoul National University | DYROS Lab | Prof. Jaeheung Park

Dec. 2022 – Feb. 2024

- Developed a Deep Reinforcement Learning framework to find optimal actuator designs for legged robots with weak actuation using model-free RL and Bayesian Optimization.
- The proposed method boosted maximum forward velocity by 19% while improving velocity tracking accuracy, and cut transportation costs by 22% by maintaining a robust symmetric gait under added-mass conditions.
- Awarded *Outstanding Thesis Presentation* (1 out of 120 graduates) [\[Paper\]](#)

Seoul National University | Soft Robotics Lab | Prof. Yong-Lae Park

Dec. 2021 – Mar. 2022

- Designed capacitive touch sensing grid as force-control interface for industrial sewing robots, increased speed by 20%.

RELATED PROJECTS

Deep Reinforcement Learning on 2D Bin Packing Problem | SNU [\[GitHub\]](#)

Aug. 2024 – Sept. 2024

- Developed custom Reinforcement Learning environment for a 2D BPP utilizing a multi-component reward function.
- Achieved an average load factor of over 0.8 under randomized input box order and squeezing constraints.

RC Car Autonomous Driving | SNU [\[GitHub\]](#)

Aug. 2023 – Nov. 2023

- Built and tested autonomous driving pipelines by implementing pure pursuit and behavior cloning for navigation.
- Deployed and fine-tuned learning control policies, achieving reliable performance on a real RC car in a racing challenge.